XeTeX template

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Contents

1 Section 1

1.1 Subsection 1

[1]

1. Item1
2. Item2
3. Item3

- Item1
- Item2
- Item3

```
for i=1 to numIterations do:
  # doSomething
  doSomething()

return X
```

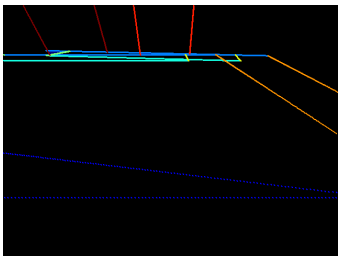
Listing 1: Python source

```
public class HelloWorld {

    public static void main(String[] args) {
        System.out.println("Hello, World");
    }

}
```

Listing 2: Java source from external file

1

$$m(line) = \frac{f_\theta\left(1-\frac{\theta}{180}\right)+f_l\left(1-\frac{l}{\sqrt{x_{img}^2+y_{img}^2}}\right)+f_o\left(\frac{o}{l_{ex}}\right)+f_d\left(1-\frac{d_1+d_2}{2\sqrt{x_{img}^2+y_{img}^2}}\right)}{f_\theta+f_l+f_o+f_d}$$



2 Section 2

References

[1] Daniel Stronger and Peter Stone. Expectation-Based Vision for Precise Self-Localization on a Mobile Robot. In *Proceedings of AAAI workshop on Cognitive Robotics*, 2006. 3