```
\begin{array}{l} \overset{s}{A} = \\ \begin{bmatrix} A_1, \dots, A_{N_U} \end{bmatrix} \\ s = \\ \begin{bmatrix} s_1; \dots; s_{N_U} \end{bmatrix} \\ x^{dl} = \tilde{x}^{dl} + Q, \end{array}
       Q = Q
                                 \begin{aligned} & \stackrel{\boldsymbol{\vee}}{[q_1, \dots, q_{N_u}]}^T \\ & q_i \mathcal{N}(0, \sigma_{q^2}) \\ & \tilde{\boldsymbol{x}}^{dl} = W P^{\frac{1}{2}} \boldsymbol{s}, \end{aligned}
                                     A
W
N<sub>r</sub>
    (3) \begin{cases} N_r \\ y_j = H \\ (3) \\ y_j \\ H_j \\ 1 \times \\ N_r \\ z_j \\ \mathcal{N}(0, 1) \\ i \end{cases}
                                                         =H_jx+z_j
                                  P_{i}(W,\sigma) = \frac{1}{T}E[||x_{i}||^{2}] = trace(w_{i}P^{\frac{1}{2}}P^{H\frac{1}{2}}w_{i}^{H} + \sigma_{q_{i}}^{2}(I))
C_{i}(W, \sigma_{q}) = \log \det(w_{i} P^{\frac{1}{2}} P^{H\frac{1}{2}} w_{i}^{H} + \sigma_{q_{i}}^{2}(I)) - N_{r} \log(\sigma_{q_{i}}^{2})
           j
                                  R(W,\sigma_q)_j = I_H(s_j,y_j) = \log \det(I + H_j(W_jW_j^H + \sigma_x \times I)H_j^H) - \log \det(I + H_j(\sum_{k \in N_u, k \neq j} W_kW_k^H + \sigma_x \times I)H_j^H) - \log \det(I + H_j(S_j,y_j) = \log \det(I + H_j(S_j,y_j) + \log \det(I + 
       (6)
I_H
                                  \max_{W,\sigma} \sum R(W,\sigma_q) subject to \bar{P}_i(W,\sigma_q) \leq P_{max} \forall i C_i(W,\sigma_q) \leq C^{th} \forall i
       (7) \\ \bar{P}_i(W, \sigma_q)
                           \begin{array}{c} r_i(v, o_q) \\ i \\ C_i(W, \sigma_q) \\ j \\ v \\ R_v \\ D_v \\ r_{(s,n)} \\ y \\ d_{(s,k)} \\ k \end{array}
                                  y_{\mathcal{D}_s} = \sum_{v=1}^{S} H_{\mathcal{R}_v, \mathcal{D}_s}^H W_{R_v, D_v} P_{D_v}^{\frac{1}{2}} x_{\mathcal{R}_v} + z_{\mathcal{D}_s},
          (8) \begin{array}{c} v=1 \\ x_{\mathcal{D}_{v}} = \\ [x_{d_{(v,1)}}, ..., x_{d_{(v,D_{v})}}]^{T} \in \\ C^{\mathcal{D} \times T} \\ T \\ W_{\mathcal{D}_{v}} = 0 \end{array}
                                                                         W_{R_v,D_v} = \,
                               \begin{array}{l} W_{R_{v},D_{v}} = \\ [w_{R_{v},d_{(v,1)}},...,w_{R_{v},d_{(v,D_{v})}}]^{T} \in \\ \mathcal{C}^{R_{v}\times D_{v}} \\ \mathcal{C}_{D_{s}} \\ z_{\mathcal{D}_{s}} \mathcal{N}(0,N_{0}I_{D_{s}}) \\ N_{0} \\ H_{R_{v},D_{s}} \\ R_{v} \\ D_{s} \\ H_{\mathcal{R}_{v},\mathcal{D}_{s}} = \\ T \end{array}
```