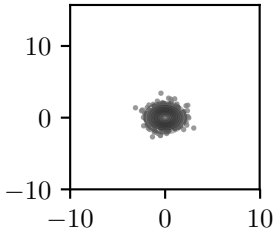
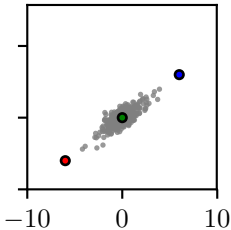


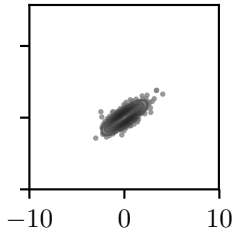
Prior: $P(Z)$



Marginal: $P(X)$



Noise 1: $P_y(Y)$



Noise 2: $P_y(Y)$

