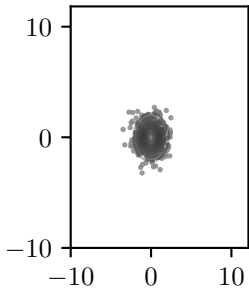
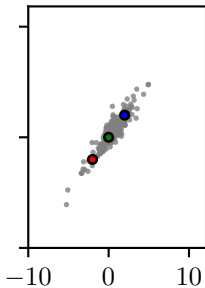


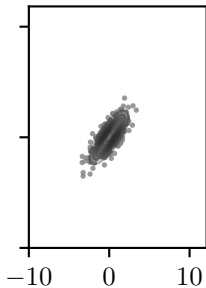
Prior:  $P(Z)$



Marginal:  $P(X)$



Noise 1:  $P_y(Y)$



Noise 2:  $P_y(Y)$

