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Density estimation of a mixture distribution with unknown point-mass and normal error

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ABSTRACT

We consider the model $Y = X + \xi$ where Y is observable, ξ is a noise random variable with density f_ξ , X has an unknown mixed density such that $\mathbb{P}(X = X_c) = 1 - p$, $\mathbb{P}(X = a) = p$ with X_c being continuous and $p \in (0, 1)$, $a \in \mathbb{R}$. Typically, in the last decade, the model has been widely considered in a number of papers for the case of fully known quantities a, f_ξ . In this paper, we relax the assumptions and consider the parametric error $\xi \sim \sigma N(0, 1)$ with an unknown $\sigma > 0$. From i.i.d. copies Y_1, \dots, Y_m of Y we will estimate (σ, p, a, f_{X_c}) where f_{X_c} is the density of X_c . We also find the lower bound of convergence rate and verify the minimax property of established estimators.

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1. Introduction

In applications, we often have the problem of finding the probability distribution of a random variable X from measurements contaminated with a noise ξ . Simplicity, we can assume the additive model $Y = X + \xi$ with Y observed. Estimation of the target density f_X of X from observations of the random variable Y is called the (statistical) deconvolution problem. The literature of the specific problem has grown very rapidly in last decades (see Devroye, 1989; Meister, 2009 and references therein). Precisely, in the present paper, we assume the data model

$$Y_j = X_j + \xi_j, \quad j = \overline{1, m}, \quad (1)$$

where the Y_j 's are i.i.d. observable copies of the random variable Y , the X_j 's and the ξ_j 's, $j = \overline{1, m}$, are mutually independent and have the same distribution as X , ξ respectively. As is well known, any estimation tool of deconvolution problem is based on a combination of presumptions about the target density function and the density function of error.

We first discuss shortly the presumption on the target density function. In the deconvolution literature, most of the research is focused on continuous distributions. However, in some applications, the target random variable X is not

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