<table>
<tr><th>目前</th><th>理论</th><th>非线性 角谱</th><th>分步 傅立叶</th></tr>
<tr><td rowspan="2">纵向</td><td>求和</td><td>$G_{3z}=\frac{\omega_3^2}{c^2}\cdot\frac{1-e^{-ik_{3z}\mathrm{dz}}}{k_{3z}^2}\cdot\sum_{j=1}^{z/\mathrm{dz}}Q_{3,z-j\cdot\mathrm{dz}}\cdot e^{ik_{3z}\cdot j\cdot\mathrm{dz}}$</td><td>$G_{3z}=\frac{\omega_3^2}{c^2}\cdot\frac{1}{\Delta k+2k_3}\cdot\frac{e^{i\Delta k\cdot\mathrm{dz}}-1}{\Delta k}\cdot\sum_{j=1}^{z/\mathrm{dz}}Q_{3,z-j\cdot\mathrm{dz}}\cdot e^{ik_{3z}\cdot j\cdot\mathrm{dz}}$</td></tr>
<tr><td>迭代</td><td>$G_{3,z+\mathrm{dz}}=\left[G_{3z}+\frac{\omega_3^2}{c^2}\cdot\frac{1-e^{-ik_{3z}\mathrm{dz}}}{k_{3z}^2}\cdot Q_{3z}\right]\cdot e^{ik_{3z}\mathrm{dz}}$</td><td>$G_{3,z+\mathrm{dz}}=\left[G_{3z}+\frac{\omega_3^2}{c^2}\cdot\frac{1}{\Delta k+2k_3}\cdot\frac{e^{i\Delta k\cdot\mathrm{dz}}-1}{\Delta k}\cdot Q_{3z}\right]\cdot e^{ik_{3z}\mathrm{dz}}$</td></tr>
<tr><td rowspan="2">横向</td><td>二维</td><td colspan="2">$G_{3z}=\frac{\chi_{\mathrm{eff}}\omega_3^2}{c^2}\frac{e^{ik_{3z}z}}{k_{3z}}\cdot\iint g_1\left(k_x,k_y\right)\cdot g_2\left(k_{3x}-k_x,k_{3y}-k_y\right)\cdot\frac{e^{i\Delta k_z z}-1}{\Delta k_z}\frac{1}{\Delta k_z/k_{3z}+2}\mathrm{d}k_x\mathrm{d}k_y$</td></tr>
<tr><td>四维</td><td colspan="2">$G_{3z}=\frac{\chi_{\mathrm{eff}}\omega_3^2}{c^2}\cdot\frac{e^{ik_{3z}z}}{k_{3z}}\cdot\sum\sum_{\substack{k_{3x}=k_{1x}+k_{2x}\\k_{3y}=k_{1y}+k_{2y}}}g_1\left(k_{1x},k_{1y}\right)\cdot g_2\left(k_{2x},k_{2y}\right)\cdot\frac{e^{i\Delta k_z z}-1}{\Delta k_z}\frac{1}{\Delta k_z/k_{3z}+2}$</td></tr>
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