





$$g(x,y,z,t) = f(x,y,z,t) \underset{x,y,z}{\otimes} k_1(x,y,z)$$

Step 2, Optical System Modeling

$$h(x,y,t) = \int g(x,y,z,t) \otimes k_2(x,y,z) dz$$

$$s(m,n,p) = h(mT_x,nT_y,pT_t) + n(m,n,p)$$
 Step 2, Optical System Modeling Step 3, Camera Sampling Modeling

 $S(m,n,\bar{p})$