$q_g(x,y,z,t)$ → $h(x,y,z,t)$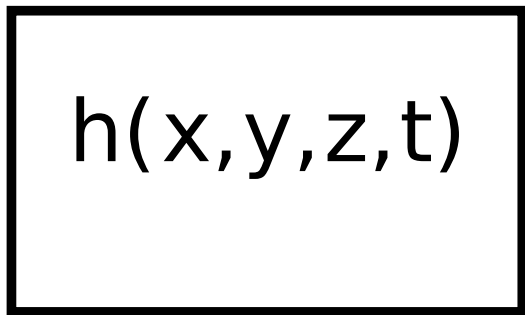 → $W(x,y,z,t)$