1D Gaussian filter

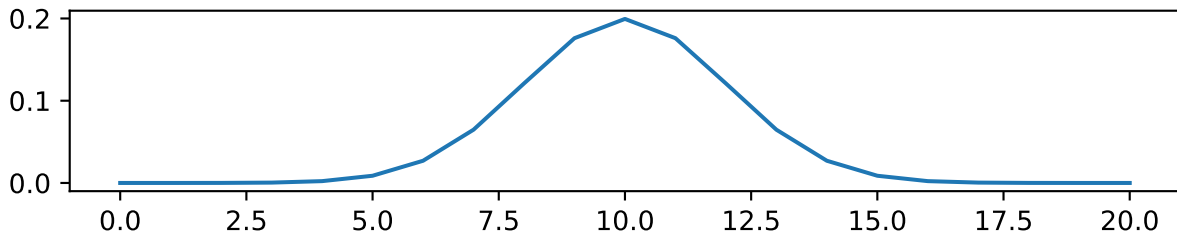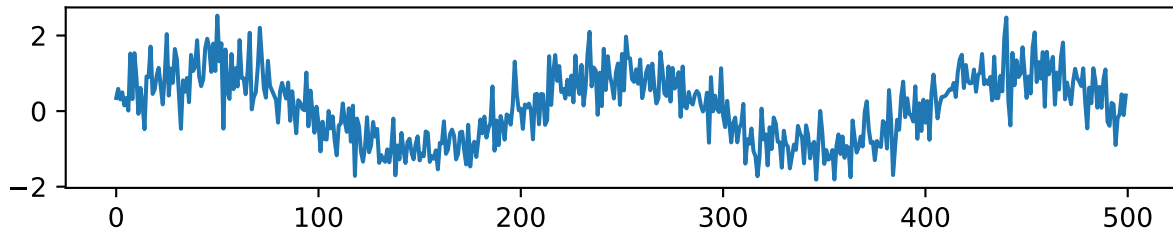**Sin + Noise**

Convolved Sin + Noise