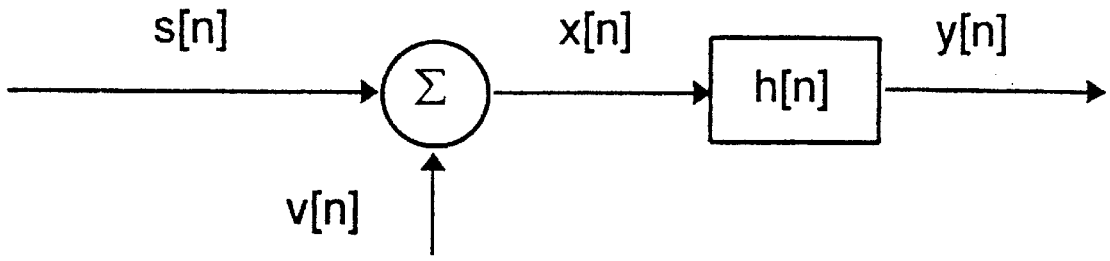
s[n]
x[n]
y[n]
Σ
h[n]
v[n]

FIG. 1

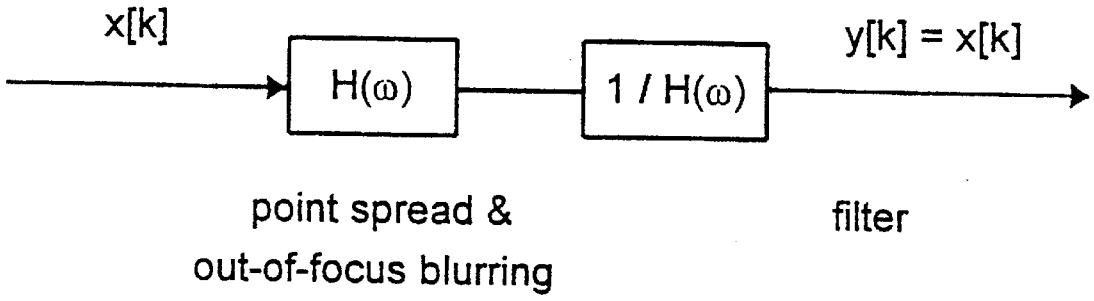
x[k]
H(ω)
1 / H(ω)
y[k] = x[k]
point spread &
out-of-focus blurring
filter

FIG. 2