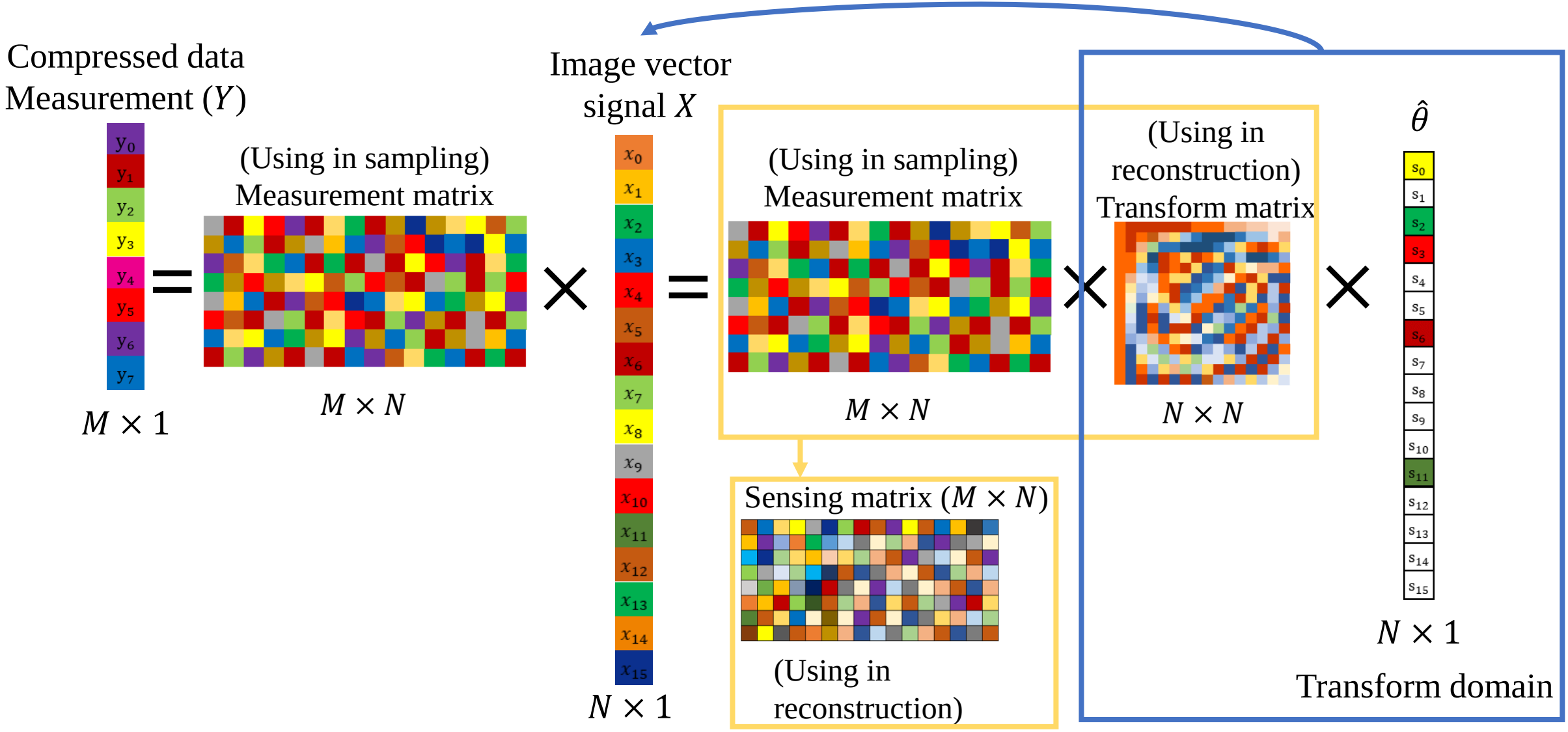
Compressed data
Measurement (Y)
y_0 y_1 y_2 y_3 y_4 y_5 y_6 y_7
$M \times 1$
=
(Using in sampling)
Measurement matrix
$M \times N$
×
Image vector
signal X
x_0 x_1 x_2 x_3 x_4 x_5 x_6 x_7 x_8 x_9 x_{10} x_{11} x_{12} x_{13} x_{14} x_{15}
$N \times 1$
=
(Using in sampling)
Measurement matrix
$M \times N$
×
(Using in
reconstruction)
Transform matrix
$N \times N$
×
$\hat{\theta}$
s_0 s_1 s_2 s_3 s_4 s_5 s_6 s_7 s_8 s_9 s_{10} s_{11} s_{12} s_{13} s_{14} s_{15}
$N \times 1$
Transform domain
Sensing matrix ($M \times N$)
(Using in
reconstruction)