1 Gaussian Optics and Uncertainty Principle

This chapter contains *Gaussian optics* and employs a matrix formalism to describe optical image formation through light rays. In optics, a ray is an idealized model of light. However, in a subsequent chapter (Chapter 3, Section 3.5), we will also see that a matrix formalism can also be used to describe, for example, a Gaussian laser beam under diffraction through the wave optics approach. The advantage of the matrix formalism is that any ray can be tracked during its propagation through the optical system by successive matrix multiplications, which can be easily programmed on a computer. This is a powerful technique and is widely used in the design of optical elements. In the chapter, some of the important concepts in resolution, depth of focus, and depth of field are also considered based on the ray approach.

1.1 Gaussian Optics

Gaussian optics, named after Carl Friedrich Gauss, is a technique in geometrical optics that describes the behavior of light rays in optical systems under the paraxial approximation. We take the *optical axis* to be along the z-axis, which is the general direction in which the rays travel, and our discussion is confined to those rays that lie in the x–z plane and that are close to the optical axis. In other words, only rays whose angular deviation from the optical axis is small are considered. These rays are called *paraxial rays*. Hence, the sine and tangent of the angles may be approximated by the angles themselves, that is, $\sin\theta \approx \tan\theta \approx \theta$. Indeed, the mathematical treatment is simplified greatly because of the linearization process involved. For example, a linearized form of *Snell's law of refraction*, $n_1 \sin\phi_i = n_2 \sin\phi_t$, is $n_1\phi_i = n_2\phi_t$. Figure 1.1-1 shows ray refraction for Snell's law. ϕ_i and ϕ_t are the angles of incidence and refraction, respectively, which are measured from the normal, ON, to the interface POQ between Media 1 and 2. Media 1 and 2 are characterized by the constant refractive indices, n_1 and n_2, respectively. In the figure, we also illustrate the *law of reflection,* that is, $\phi_i = \phi_r$, where ϕ_r is the *angle of reflection*. Note that the incident ray, the refracted ray, and the reflected ray all lie in the same *plane of incidence*.

Consider the propagation of a paraxial ray through an optical system as shown in Figure 1.1-2. A ray at a given z-plane may be specified by its height x from the optical axis and by its launching angle θ. The convention for the angle is that θ is measured in radians and is anticlockwise positive from the z-axis. The quantities (x, θ) represent the

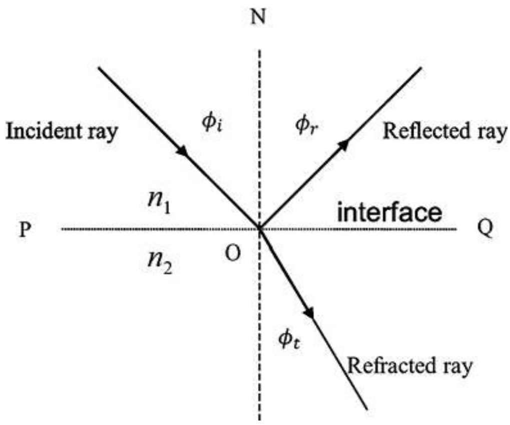


Figure 1.1-1 Geometry for Snell's law and law of reflection

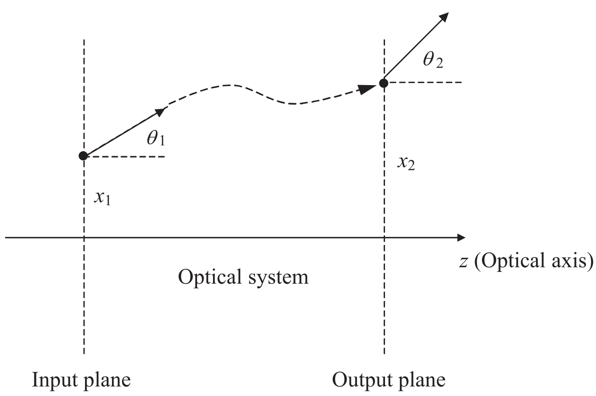


Figure 1.1-2 Ray propagating in an optical system

coordinates of the ray for a given z-plane. However, instead of specifying the angle the ray makes with the z-axis, another convention is used. We replace the angle θ by the corresponding $v = n\theta$, where n is the refractive index of the medium in which the ray is traveling. As we will see later, the use of this convention ensures that all the matrices involved are positive unimodular. A *unimodular matrix* is a real square matrix with determinant +1 or −1, and a positive unimodular matrix has determinant +1.

To clarify the discussion, we let a ray pass through the input plane with the *input ray coordinates* $(x_1, v_1 = n_1\theta_1)$. After the ray passes through the optical system, we denote the *output ray coordinates* $(x_2, v_2 = n_2\theta_2)$ on the output plane. In the paraxial approximation, the corresponding output quantities are linearly dependent on the input quantities. In other words, the output quantities can be expressed in terms of the weighted sum of the input quantities (known as the *principle of superposition*) as follows:

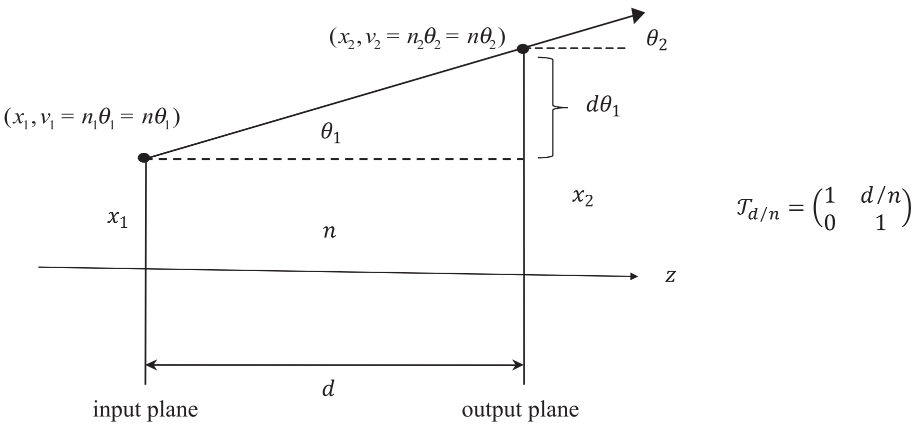


Figure 1.1-3 Ray propagating in a homogeneous medium with the input and output coordinates $(x_1, v_1 = n_1\theta_1)$ and $(x_2, v_2 = n_2\theta_2)$, respectively

$$x_2 = Ax_1 + Bv_1 \text{ and } v_2 = Cx_1 + Dv_1,$$

where A, B, C, and D are the weight factors. We can cast the above equations into a matrix form as

$$\begin{pmatrix} x_2 \\ v_2 \end{pmatrix} = \begin{pmatrix} A & B \\ C & D \end{pmatrix} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix}. \quad (1.1\text{-}1)$$

The *ABCD* matrix in Eq. (1.1-1) is called the *ray transfer matrix*, or the *system matrix* S, if it is represented by the multiplication of ray transfer matrices. In what follows, we shall derive several important ray transfer matrices.

1.1.1 Ray Transfer Matrices

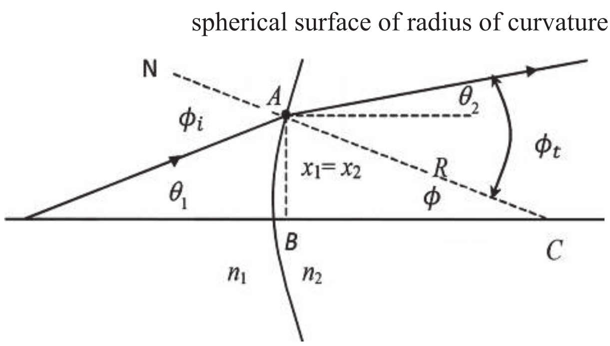
Translation Matrix

A ray travels in a homogenous medium of refractive index n in a straight line (see Figure 1.1-3). Let us denote the input and output planes with the ray's coordinates, and then we try to relate the input and output coordinates with a matrix after the traveling of the distance d. Since $n_1 = n_2 = n$ and $\theta_1 = \theta_2, v_2 = n_2\theta_2 = n_1\theta_1 = v_1$. From the geometry, we also find $x_2 = x_1 + d\tan\theta_1 \approx x_1 + d\theta_1 = x_1 + dv_1/n$. Therefore, we can relate the output coordinates of the ray with its input coordinates as follows:

$$\begin{pmatrix} x_2 \\ v_2 \end{pmatrix} = \begin{pmatrix} 1 & d/n \\ 0 & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix} = \mathcal{T}_{d/n} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix}, \quad (1.1\text{-}2)$$

where

$$\mathcal{T}_{d/n} = \begin{pmatrix} 1 & d/n \\ 0 & 1 \end{pmatrix}, \quad (1.1\text{-}3a)$$



$$\mathcal{R}_R = \begin{pmatrix} 1 & 0 \\ \dfrac{n_1 - n_2}{R} & 1 \end{pmatrix}$$

Figure 1.1-4 Ray trajectory during refraction at a spherical surface separating two regions of refractive indices n_1 and n_2

which is called the *translation matrix*. The matrix describes the translation of a ray for a distance d along the optical axis in a homogenous medium of n. The determinant of $\mathcal{T}_{d/n}$ is

$$\left|\mathcal{T}_{d/n}\right| = \begin{vmatrix} 1 & d/n \\ 0 & 1 \end{vmatrix} = 1,$$

and hence $\mathcal{T}_{d/n}$ is a positive unimodular matrix. For a translation of the ray in air, we have $n = 1$, and the translation can be represented simply by

$$\mathcal{T}_d = \begin{pmatrix} 1 & d \\ 0 & 1 \end{pmatrix}. \quad (1.1\text{-}3b)$$

Refraction Matrix

We consider a spherical surface separating two regions of refractive indices n_1 and n_2 as shown in Figure 1.1-4. The center of the spherical surface is at C, and its radius of curvature is R. The convention for the *radius of curvature* is as follows. The radius of curvature of the surface is taken to be positive (negative) if the center C of curvature lies to the right (left) of the surface. The ray strikes the surface at the point A and gets refracted into media n_2. Note that the input and output planes are the same. Hence, the height of the ray at A, before and after refraction, is the same, that is, $x_2 = x_1$. ϕ_i and ϕ_t are the angles of incidence and refraction, respectively, which are measured from the normal NAC to the curved surface. Applying Snell's law and using the paraxial approximation, we have

$$n_1\phi_i = n_2\phi_t. \quad (1.1\text{-}4)$$

Now, from geometry, we know that $\phi_i = \theta_1 + \phi$ and $\phi_t = \theta_2 + \phi$ (Figure 1.1-4). Hence, the left side of Eq. (1.1-4) becomes

$$n_1\phi_i = n_1(\theta_1 + \phi) = v_1 + n_1 x_1 / R, \quad (1.1\text{-}5)$$

where we have used $\sin\phi = x_1 / R \approx \phi$. Now, the right side of Eq. (1.1-4) is

$$n_2\phi_t = n_2(\theta_2 + \phi) = v_2 + n_2 x_2 / R, \tag{1.1-6}$$

where $x_1 = x_2$ as the input and output planes are the same.

Finally, putting Eqs. (1.1-5) and (1.1-6) into Eq. (1.1-4), we have

$$v_1 + n_1 x_1 / R = v_2 + n_2 x_2 / R$$

or

$$v_2 = v_1 + \left(n_1 - n_2\right) x_1 / R, \quad \text{as} \quad x_1 = x_2. \tag{1.1-7}$$

We can formulate the above equation in terms of a matrix equation as

$$\begin{pmatrix} x_2 \\ v_2 \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ \dfrac{n_1 - n_2}{R} & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ -p & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix} = \mathcal{R}_R \begin{pmatrix} x_1 \\ v_1 \end{pmatrix}, \tag{1.1-8}$$

where

$$\mathcal{R}_R = \begin{pmatrix} 1 & 0 \\ -p & 1 \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ \dfrac{n_1 - n_2}{R} & 1 \end{pmatrix}.$$

The determinant of $\mathcal{R}_R$ is

$$|\mathcal{R}_R| = \begin{vmatrix} 1 & 0 \\ -p & 1 \end{vmatrix} = 1.$$

The 2 × 2 ray transfer matrix $\mathcal{R}_R$ is a positive unimodular matrix and is called the *refraction matrix*. The matrix describes refraction for the spherical surface. The quantity p given by

$$p = \frac{n_2 - n_1}{R}$$

is called the *refracting power* of the spherical surface. When R is measured in meters, the unit of p is called *diopters*. If an incident ray is made to converge on (diverge from) by a surface, the power is positive (negative) in sign.

Thick- and Thin-Lens Matrices

A thick lens consists of two spherical surfaces as shown in Figure 1.1-5. We shall find the system matrix that relates the system's input coordinates $\left(x_1, v_1\right)$ to system's output ray coordinates (x_2, v_2). Let us first relate (x_1, v_1) to (x_1', v_1') through the spherical surface defined by R_1. (x_1', v_1') are the output coordinates due to the surface R_1. According to Eq. (1.1-8), we have

$$\begin{pmatrix} x_1' \\ v_1' \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ \dfrac{n_1 - n_2}{R_1} & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix} = \mathcal{R}_{R_1} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix}. \tag{1.1-9}$$

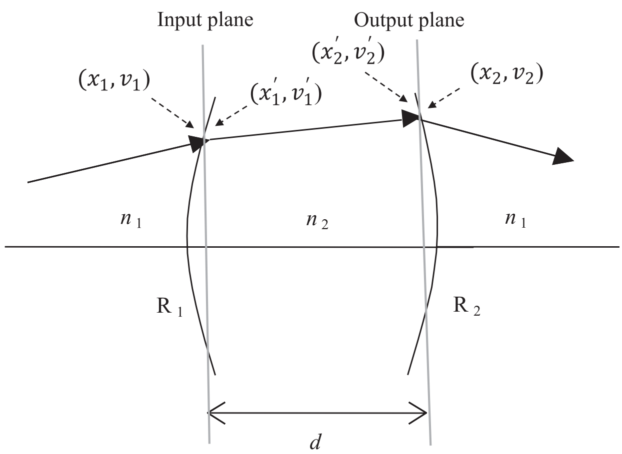


Figure 1.1-5 Thick lens

Now, (x_1', v_1') and (x_2', v_2') are related through a translation matrix as follows:

$$\begin{pmatrix} x_2' \\ v_2' \end{pmatrix} = \begin{pmatrix} 1 & d/n_2 \\ 0 & 1 \end{pmatrix} \begin{pmatrix} x_1' \\ v_1' \end{pmatrix} = \mathcal{T}_{d/n_2} \begin{pmatrix} x_1' \\ v_1' \end{pmatrix}, \tag{1.1-10}$$

where (x_2', v_2') are the output coordinates after translation, which are also the coordinates of the input coordinates for the surface R_2. Finally, we relate (x_2', v_2') to the system's output coordinates (x_2, v_2) through

$$\begin{pmatrix} x_2 \\ v_2 \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ \dfrac{n_2 - n_1}{R_2} & 1 \end{pmatrix} \begin{pmatrix} x_2' \\ v_2' \end{pmatrix} = \mathcal{R}_{-R_2} \begin{pmatrix} x_2' \\ v_2' \end{pmatrix}. \tag{1.1-11}$$

If we now substitute Eq. (1.1-10) into Eq. (1.1-11), then we have

$$\begin{pmatrix} x_2 \\ v_2 \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ \dfrac{n_2 - n_1}{R_2} & 1 \end{pmatrix} \begin{pmatrix} 1 & d/n_2 \\ 0 & 1 \end{pmatrix} \begin{pmatrix} x_1' \\ v_1' \end{pmatrix}.$$

Subsequently, substituting Eq. (1.1-9) into the above equation, we have the *system matrix equation* of the entire system as follows:

$$\begin{aligned} \begin{pmatrix} x_2 \\ v_2 \end{pmatrix} &= \begin{pmatrix} 1 & 0 \\ \dfrac{n_2 - n_1}{R_2} & 1 \end{pmatrix} \begin{pmatrix} 1 & \dfrac{d}{n_2} \\ 0 & 1 \end{pmatrix} \begin{pmatrix} 1 & 0 \\ \dfrac{n_1 - n_2}{R_1} & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix} \\ &= \mathcal{R}_{-R_2} \mathcal{T}_{d/n_2} \mathcal{R}_{R_1} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix} = \mathcal{S} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix}. \end{aligned} \tag{1.1-12}$$

We have now finally related the system's input coordinates to output coordinates. Note that the system matrix, $\mathcal{S} = \mathcal{R}_{-R_2} \mathcal{T}_{d/n_2} \mathcal{R}_{R_1}$, is a product of three ray transfer matrices. In general, the system matrix is made up of a collection of ray transfer matrices to account for the effects of a ray passing through the optical system. As the ray goes from left to right in the positive direction of the z-axis, we obtain the system matrix by writing the ray transfer matrices from right to left. This is precisely the advantage of the matrix formalism in that any ray, during its propagation through the optical system, can be tracked by successive matrix multiplications. Let $\mathcal{A}$ and $\mathcal{B}$ be the 2 × 2 matrices as follows:

$$\mathcal{A} = \begin{pmatrix} a & b \\ c & d \end{pmatrix} \text{ and } \mathcal{B} = \begin{pmatrix} e & f \\ g & h \end{pmatrix}.$$

Then the rule of matrix multiplication is

$$\mathcal{AB} = \begin{pmatrix} a & b \\ c & d \end{pmatrix}\begin{pmatrix} e & f \\ g & h \end{pmatrix} = \begin{pmatrix} ae+bg & af+bh \\ ce+dg & cf+dh \end{pmatrix}.$$

Now, returning to the system matrix in Eq. (1.1-12), the determinant of the system matrix, $\mathcal{S} = \mathcal{R}_{-R_2}\mathcal{T}_{d/n_2}\mathcal{R}_{R_1}$, is

$$|\mathcal{S}| = \left|\mathcal{R}_{-R_2}\mathcal{T}_{d/n_2}\mathcal{R}_{R_1}\right| = \left|\mathcal{R}_{-R_2}\right| \times \left|\mathcal{T}_{d/n_2}\right| \times \left|\mathcal{R}_{R_1}\right| = 1.$$

Note that even the system matrix is also positive unimodular. The condition of a unit determinant is a necessary but not a sufficient condition on the system matrix.

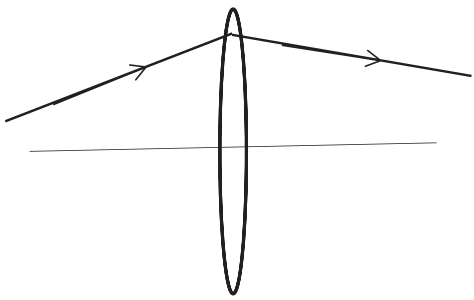
We now derive a matrix of an idea thin lens of focal length f, called the *thin-lens matrix*, $\mathcal{L}_f$. For a thin lens in air, we let $d \to 0$ and $n_1 = 1$ in the configuration of Figure 1.1-5. We also write $n_2 = n$ for notational convenience. Then the system matrix in Eq. (1.1-12) becomes

$$\begin{aligned} \mathcal{S} &= \begin{pmatrix} 1 & 0 \\ \dfrac{n-1}{R_2} & 1 \end{pmatrix}\begin{pmatrix} 1 & 0 \\ 0 & 1 \end{pmatrix}\begin{pmatrix} 1 & 0 \\ \dfrac{1-n}{R_1} & 1 \end{pmatrix} \\ &= \begin{pmatrix} 1 & 0 \\ \dfrac{n-1}{R_2} & 1 \end{pmatrix}\begin{pmatrix} 1 & 0 \\ \dfrac{1-n}{R_1} & 1 \end{pmatrix} \\ &= \begin{pmatrix} 1 & 0 \\ -\dfrac{1}{f} & 1 \end{pmatrix} = \mathcal{L}_f, \end{aligned} \tag{1.1-13}$$

where f is the *focal length* of the thin lens and is given by

$$\frac{1}{f} = (n-1)\left(\frac{1}{R_1} - \frac{1}{R_2}\right).$$

For $f > 0$, we have a converging (convex) lens. On the other hand, we have a diverging (concave) lens when $f < 0$. Figure 1.1-6 summarizes the result for the ideal thin lens.



$$\mathcal{L}_f = \begin{pmatrix} 1 & 0 \\ -\dfrac{1}{f} & 1 \end{pmatrix}$$

Convex : $f > 0$; Concave : $f < 0$

Figure 1.1-6 Ideal thin lens of focal length f and its associated ray transfer matrix

Note that the determinant of $\mathcal{L}_f$ is

$$|\mathcal{L}_f| = \begin{vmatrix} 1 & 0 \\ -\dfrac{1}{f} & 1 \end{vmatrix} = 1.$$

1.1.2 Ray Tracing through a Thin Lens

As we have seen from Section 1.1.1, when a thin lens of focal length f is involved, then the matrix equation, from Eq. (1.1-13), is

$$\begin{pmatrix} x_2 \\ v_2 \end{pmatrix} = \mathcal{L}_f \begin{pmatrix} x_1 \\ v_1 \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ -\dfrac{1}{f} & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ v_1 \end{pmatrix}. \tag{1.1-14}$$

Input Rays Traveling Parallel to the Optical Axis

From Figure 1.1-7a, we recognize that $x_1 = x_2$ as the heights of the input and output rays are the same for the thin lens. Now, according to Eq. (1.1-14), $v_2 = -x_1 / f + v_1$. For $v_1 = 0$, that is, the input rays are parallel to the optical axis, $v_2 = -x_1 / f$. For positive $x_1, v_2 < 0$ as $f > 0$ for a converging lens. For negative $x_1, v_2 > 0$. All input rays parallel to the optical axis converge behind the lens to the back focal point (a distance of f away from the lens) of the lens as shown in Figure 1.1-7a. Note that for a thin lens, the front focal point is also a distance of f away from the lens.

Input Rays Traveling through the Center of the Lens

For input rays traveling through the center of the lens, their input ray coordinates are $(x_1, v_1) = (0, v_1)$. The output ray coordinates, according to Eq. (1.1.14), are $(x_2, v_2) = (0, v_1)$. Hence, we see as $v_2 = v_1$, all rays traveling through the center of the lens will pass undeviated as shown in Figure 1.1-7b.

Cambridge University Press & Assessment
978-1-316-51159-6 — Modern Information Optics with MATLAB
Yaping Zhang , Ting-Chung Poon
Excerpt
More Information

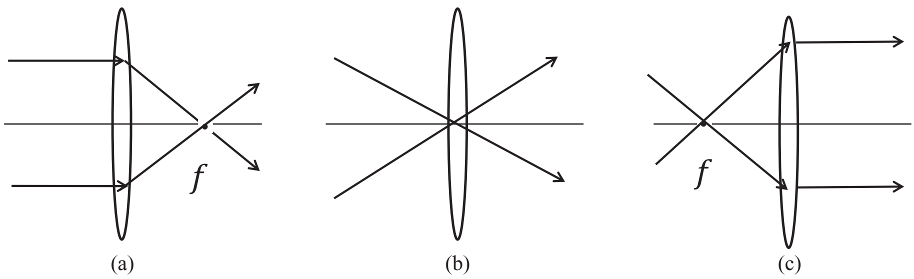


Figure 1.1-7 Ray tracing through a thin convex lens

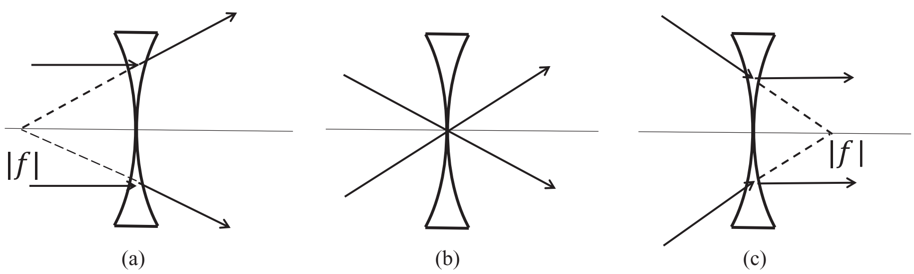


Figure 1.1-8 Ray tracing through a thin concave lens

Input Rays Passing through the Front Focal Point of the Lens

For this case, the input ray coordinates are $(x_1, v_1 = x_1 / f)$, and, according to Eq. (1.1-14), the output ray coordinates are $(x_2 = x_1, v_2 = 0)$, which means that all output rays will be parallel to the optical axis $(v_2 = 0)$, as shown in Figure 1.1-7c.

Similarly, in the case of a diverging lens, we can draw conclusions as follows. The ray after refraction diverges away from the axis as if it were coming from a point on the axis a distance $|f|$ in front of the lens, as shown in Figure 1.1-8a. The ray traveling through the center of the lens will pass undeviated, as shown in Figure 1.1-8b. Finally, for an input ray appearing to travel toward the back focus point of a diverging lens, the output ray will be parallel to the optical axis, as shown in Figure 1.1-8c.

Example: Imaging by a Convex Lens

We consider a single-lens imaging as shown in Figure 1.1-9, where we assume the lens is immersed in air. We first construct a *ray diagram* for the imaging system. An object OO′ is located a distance d_0 in front of a thin lens of focal length f. We send two rays from a point O′ towards the lens. Ray 1 from O′ is incident parallel to the optical axis, and from Figure 1.1-7a, the input ray parallel to the optical axis converges behind the lens to the back focal point. A second ray, that is, ray 2 also from O′, is now drawn through the center of the lens without bending and that is the result from Figure 1.1-7b. The interception of the two rays on the other side of the lens forms an image point of O′. The image point of O′ is labeled at I′ in the diagram. The final image is real, inverted, and is called a *real image.*

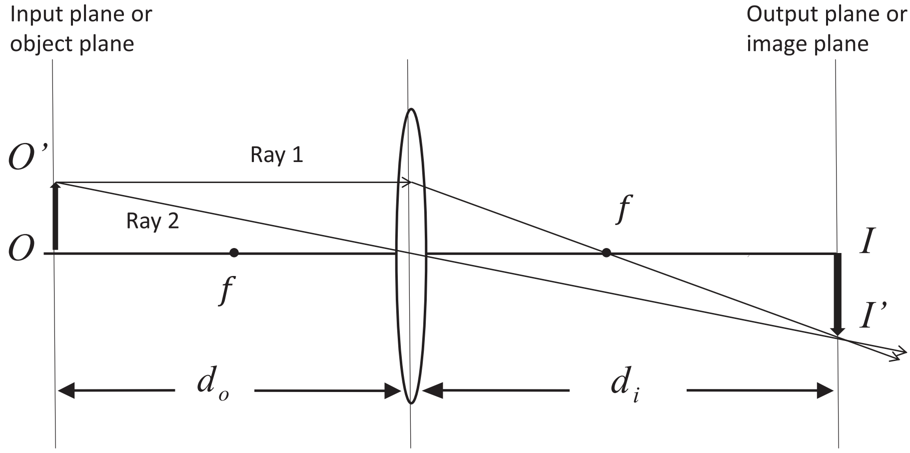


Figure 1.1-9 Ray diagram for single-lens imaging

Now we investigate the imaging properties of the single thin lens using the matrix formalism. The input plane and the output plane of the optical system are shown in Figure 1.1-9. We let (x_0, v_0) and (x_i, v_i) represent the coordinates of the ray at O′ and I′, respectively. We see there are three matrices involved in the problem. The overall system matrix equation becomes

$$\begin{pmatrix} x_i \\ v_i \end{pmatrix} = \mathcal{T}_{d_i}\mathcal{L}_f\mathcal{T}_{d_0}\begin{pmatrix} x_0 \\ v_0 \end{pmatrix} = \mathcal{S}\begin{pmatrix} x_0 \\ v_0 \end{pmatrix}. \tag{1.1-15}$$

The overall system matrix,

$$\mathcal{S} = \mathcal{T}_{d_i}\mathcal{L}_f\mathcal{T}_{d_0} = \begin{pmatrix} 1 & d_i \\ 0 & 1 \end{pmatrix}\begin{pmatrix} 1 & 0 \\ -\dfrac{1}{f} & 1 \end{pmatrix}\begin{pmatrix} 1 & d_0 \\ 0 & 1 \end{pmatrix},$$

is expressed in terms of the product of three matrices written in order from right to left as the ray goes from left to right along the optical axis, as explained earlier. According to the rule of matrix multiplication, Eq. (1.1-15) can be simplified to

$$\begin{pmatrix} x_i \\ v_i \end{pmatrix} = \begin{pmatrix} 1 - d_i / f & d_0 + d_i - d_0 d_i / f \\ -\dfrac{1}{f} & 1 - d_0 / f \end{pmatrix}\begin{pmatrix} x_0 \\ v_0 \end{pmatrix} = \begin{pmatrix} A & B \\ C & D \end{pmatrix}\begin{pmatrix} x_0 \\ v_0 \end{pmatrix}. \tag{1.1-16}$$

To investigate the conditions for imaging, let us concentrate on the *ABCD* matrix of $\mathcal{S}$ in Eq. (1.1-16). In general, we see that $x_i = Ax_0 + Bv_0 = Ax_0$ if $B = 0$, which means that all rays passing through the input plane at the same object point x_0 will pass through the same image point x_i in the output plane. This is the condition of *imaging*. In addition, for $B = 0$, $A = x_i / x_0$ is defined as the *lateral magnification* of