# smam: Statistical Modeling for Animal Movements

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#### 1. Introduction

This package is designed for animal movement analysis. We totally implemented three models, Brownian motion with measurement error [4], moving-resting process with embedded Brownian motion [1,2], and moving-resting-hunting process with embedded Brownian motion [3]. These three models can also be fitted with specific parts of dataset, which is called segment estimation in this vignette. From the perspective of ecology and animal movement, segment estimation can be hired for seasonal analysis. We also provided toolbox for seasonal analysis within this package, which can subset data according to given date interval.

In this vignette, we play with the GPS dataset of a mountain lion and quantify her movement behavior. First of all, let us take a look at the dataset.

```
library(smam)
head(f109)
```

```
##
           date
                      time centerE centerN
## 1 2009-01-18
                  1.000000
                                0.0
                                        0.0
## 2 2009-01-18
                  2.000000
                                0.0
                                       -0.1
## 3 2009-01-18
                  3.016667
                                       -0.1
                                0.0
## 4 2009-01-23 27.000000
                                       -0.4
                               -0.4
## 5 2009-01-24 34.983333
                                       -1.1
                                0.3
## 6 2009-01-25 42.983333
                               -0.8
                                       -0.3
```

The first column, 'date', is the date when the observation is collected. The second column, 'time', is the corresponding time line of observations. The last two columns, 'centerE' and 'centerN', are the GPS coordinates.

## 2. Whole dataset analysis

In this section, we are going to show how to use whole dataset to fit BMME, moving-resting model and moving-resting-handling model with R function fitBMME, fitMR and fitMRH. Let's see the standard format of dataset used by these functions first. It should be a data.frame whose first column is the observation time and the other columns are the location coordinates, as showing below.

```
dat1 <- f109[, -1]
head(dat1)</pre>
```

```
##
          time centerE centerN
## 1
      1.000000
                    0.0
                            0.0
## 2 2.000000
                    0.0
                           -0.1
## 3 3.016667
                           -0.1
                    0.0
## 4 27.000000
                   -0.4
                           -0.4
## 5 34.983333
                    0.3
                           -1.1
## 6 42.983333
                   -0.8
                           -0.3
```

Now, we can fit the above data by the following code. (We do not show the result, because the estimation process for moving-resting-handling model is time consuming and maybe take several hours.)

```
## fit BMME model
fitBMME(dat1, start = c(0.5, 0.5))

## fit moving-resting model with full likelihood
fitMR(dat1, start = c(10, 0.1, 1), likelihood = "full")

## fit moving-resting model with composite likelihood
fitMR(dat1, start = c(10, 0.1, 1), likelihood = "composite")

## fit moving-resting-handling model (serial computation)
## numThread is less or equal to 1 will call serial computation
fitMRH(dat1, start = c(4, 0.4, 0.1, 1, 0.5), numThreads = 1)

## fit moving-resting-handling model (parallel computation)
## numThread is greater or equal to 2 will call parallel computation
## with given number of threads
fitMRH(dat1, start = c(4, 0.4, 0.1, 1, 0.5), numThreads = 4)
```

We also mention that the sampling functions, rBMME, rMR, and rMRH, are given for BMME model, moving-resting model and moving-resting-handling model.

### 3. Segment dataset analysis

In this section, we are going to show the usage of segment estimation. In contrast with whole data estimation, the segment estimation only use part of observations. Segment estimation evaluates the likelihood for each segments of observation and sums them together as the likelihood be used in MLE process. So, in order to use segment estimation, we should tell R which part of observations we are going to use by adding additional 0-n column, where n can be any non-zero integer. The 0's in this column means discard this observation and other non-zero integers are the labels for each segments.

```
## the name of segment indicator column can be given by user
batch <- c(rep(0, 30), rep(1, 40), rep(0, 20), rep(2, 30), rep(0, 80))
dat2 <- cbind(dat1, batch) ## the result of dat2 is shown in appendix.</pre>
```

Then, when we apply fitBMME, fitMR, fitMRH on dat2, only segment 1 (batch = 1) and segment 2 (batch = 2) will be used. Then, we are going to show the code for fit these three models. (Note that, the name of indicator column should be set in segment.)

```
## fit BMME model
fitBMME(dat2, start = c(0.5, 0.5), segment = "batch")

## fit moving-resting model with full likelihood
fitMR(dat2, start = c(10, 0.1, 1), segment = "batch", likelihood = "full")

## fit moving-resting model with composite likelihood
fitMR(dat2, start = c(10, 0.1, 1), segment = "batch", likelihood = "composite")

## fit moving-resting-handling model
fitMRH(dat2, start = c(4, 0.4, 0.1, 1, 0.5), segment = "batch", numThreads = 2)
```

#### 4. Prediction of hidden states

The code for prediction of hidden states is still in process. But you can try and explore them with ?fitStateMR and ?fitStateMRH.

### References

- [1] Yan, J., Chen, Y., Lawrence-Apfel, K., Ortega, I. M., Pozdnyakoc, V., Williams, S., and Meyer, T. (2014) A moving-resting process with an embedded Brownian motion for animal movements. Population Ecology. 56(2): 401–415. doi:10.1007/s10144-013-0428-8
- [2] Pozdnyakov, V., Elbroch, L., Labarga, A., Meyer, T., and Yan, J. (2017) Discretely observed Brownian motion governed by telegraph process: estimation. Methodology and Computing in Applied Probability. doi:10.1007/s11009-017-9547-6.
- [3] Pozdnyakov, V., Elbroch, L., Hu, C., Meyer, T., and Yan, J. (2018+) On estimation for Brownian motion governed by telegraph process with multiple off states. <arXiv:1806.00849>
- [4] Pozdnyakov, V., Meyer, T., Wang, Y. and Yan, J. (2014), On modeling animal movements using Brownian motion with measurement error. Ecology, 95: 247-253. doi:10.1890/13-0532.1

# Appendix

We show the data for segment estimation here.

dat2

##		time	centerE	centerN	batch
##	1	1.000000	0.0	0.0	0
##	2	2.000000	0.0	-0.1	0
##	3	3.016667	0.0	-0.1	0
##	4	27.000000	-0.4	-0.4	0
##	5	34.983333	0.3	-1.1	0
##	6	42.983333	-0.8	-0.3	0
##	7	50.983333	-0.8	-0.3	0
##	8	58.983333	-0.8	-0.3	0
##	9	66.966667	0.1	-0.4	0
##	10	74.966667	-1.2	-2.8	0
##	11	82.966667	-1.3	-2.9	0
##	12	90.966667	-1.3	-2.9	0
##	13	98.966667	-1.3	-2.9	0
##	14	106.966667	-1.3	-2.9	0
##	15	114.966667	-1.0	-2.7	0
##	16	131.000000	-1.3	-2.9	0
##	17	138.983333	0.4	-3.6	0
##	18	146.983333	-1.1	-3.5	0
##	19	154.966667	-0.7	-4.3	0
##	20	162.966667	-0.7	-4.4	0
##	21	170.966667	-0.7	-4.4	0
##	22	178.966667	-0.7	-4.5	0
##	23	186.966667	-0.7	-4.5	0
##	24	194.966667	-0.7	-4.4	0
##	25	202.966667	-0.7	-4.4	0
##	26	210.966667	-0.7	-4.4	0
##	27	218.966667	-0.5	-4.3	0
##	28	226.983333	-0.7	-4.4	0
##	29	234.966667	-0.7	-4.5	0
##	30	242.966667	-0.4	-4.5	0
##	31	250.966667	-0.2	-4.5	1
##	32	258.966667	-0.3	-4.6	1
##	33	266.966667	-0.5	-5.9	1
##	34	274.966667	-0.5	-5.9	1
##	35	282.966667	-0.7	-4.5	1
##	36	291.000000	-0.3	-4.3	1
##	37	314.966667	-0.4	-4.4	1
##	38	322.966667	-0.4	-3.2	1

##	39	330.983333	1.7	-0.4	1
##	40	339.000000	2.4	0.5	1
##	41	346.983333	2.4	0.6	1
##	42	354.983333	2.4	0.6	1
##	43	362.966667	2.4	0.6	1
##	44	370.966667	2.4	0.5	1
##	45	378.966667	2.3	0.6	1
##	46	386.966667	2.3	0.6	1
##	47	394.983333	2.4	0.6	1
##	48	402.983333	2.4	0.6	1
##	49	410.983333	2.4	0.6	1
##	50	418.983333	2.3	0.6	1
##	51	426.983333	2.3	0.6	1
##	52	434.983333	2.3	0.6	1
##	53	442.966667	3.8	1.6	1
##	54	450.966667	3.6	0.3	1
##	55	458.983333	3.4	0.7	1
##	56	466.966667	5.3	1.4	1
##	57	474.966667	3.5	0.3	1
##	58	482.983333	3.7	0.6	1
##	59	490.983333	3.5	0.3	1
##	60	507.000000	3.5	0.3	1
##	61	514.966667	4.1	1.0	1
##	62	522.966667	3.5	0.3	1
##	63	530.966667	3.7	0.7	1
##	64	538.983333	3.7	0.7	1
##	65	546.966667	3.5	0.3	1
##	66	554.966667	3.5	0.9	1
##	67	562.966667	3.5	0.9	1
##	68	570.966667	3.4	0.8	1
##	69	586.966667	3.5	0.8	1
##	70	594.966667	3.4	0.8	1
##	71	602.983333	3.6	1.0	0
##	72	610.966667	3.6	1.0	0
##	73	618.966667	3.5	0.8	0
##	74	634.966667	3.6	1.0	0
##	75	642.966667	5.4	0.9	0
##	76	650.983333	6.3	1.5	0
##	77 70	658.966667	6.3	1.5	0
##	78 70	666.966667	4.9	0.8	0
##	79	674.983333	5.0	0.8	0
##	80	682.966667	5.0	0.8	0
##	81	690.983333	4.7	0.4	0
##	82	698.983333	5.1	1.0	0
##	83	706.966667	5.1	1.0	0

##	84	714.966667	4.0	0.4	0
##	85	722.983333	2.6	0.4	0
##	86	730.966667	2.6	0.4	0
##	87	738.966667	2.7	0.4	0
##	88	754.966667	3.6	1.0	0
##	89	762.966667	2.9	0.4	0
##	90	778.966667	2.7	0.5	0
##	91	787.000000	2.7	0.4	2
##	92	794.983333	3.6	0.9	2
##	93	802.966667	3.9	-0.3	2
##	94	810.966667	3.2	0.3	2
##	95	818.983333	3.1	0.4	2
##	96	826.966667	3.2	0.4	2
##	97	834.966667	3.2	0.3	2
##	98	842.983333	3.6	1.0	2
##	99	850.983333	3.6	0.8	2
##	100	858.966667	3.2	0.3	2
##	101	866.966667	3.6	0.7	2
##	102	874.966667	3.5	0.8	2
##	103	882.983333	3.2	0.3	2
##	104	891.000000	3.8	0.9	2
##	105	898.966667	3.9	1.0	2
##	106	906.966667	2.9	0.2	2
##	107	914.983333	2.6	0.3	2
##	108	922.966667	2.7	0.2	2
##	109	930.966667	2.9	0.2	2
##	110	939.000000	2.7	0.2	2
##	111	946.966667	2.7	0.2	2
##	112	954.966667	2.9	0.2	2
##	113	970.966667	3.0	0.4	2
##	114	994.950000	4.5	0.7	2
##		1002.966667	4.9	0.8	2
##		1018.966667	5.2	0.9	2
##	117		4.9	1.1	2
##	118		6.4	1.4	2
##	119		6.5	1.4	2
##	120		6.5	1.5	2
##	121		8.2	0.5	0
##	122	1082.950000	6.6	1.7	0
##	123		7.1	3.1	0
##	124		6.4	2.1	0
##	125		6.5	1.7	0
##		1138.916667	5.2	0.9	0
##	127	1146.883333	4.3	0.7	0
##	128	1162.883333	4.3	0.8	0

##	129	1170.883333	4.3	0.8	0
##	130	1178.916667	4.3	0.9	0
##	131	1186.916667	4.3	0.8	0
##	132	1194.883333	4.3	0.8	0
##	133	1202.916667	4.3	0.7	0
##	134	1210.883333	4.4	1.1	0
##	135		4.3	0.7	0
##	136	1226.900000	4.3	0.7	0
##	137		3.7	1.1	0
##	138		4.3	0.7	0
##	139		4.3	1.1	0
##	140		4.2	1.4	0
##	141	1266.883333	4.3	0.7	0
##	142		4.3	0.7	0
##	143		4.1	1.3	0
##	144		3.9	0.4	0
##	145		5.2	1.0	0
##	146	1322.850000	5.1	0.9	0
##	147		5.2	0.9	0
##	148		6.4	1.6	0
##	149		6.4	1.9	0
##	150		6.5	1.9	0
##	151	1362.850000	8.0	0.4	0
##	152		10.3	-1.0	0
##	153		10.4	-1.1	0
##	154		9.1	-3.7	0
##	155		9.3	-5.2	0
##	156		8.9	-5.5	0
##	157		9.4	-3.6	0
##	158		9.1	-3.6	0
##	159		9.1	-3.7	0
##		1434.833333	7.2	-1.5	0
##	161		7.1	-1.8	0
##		1450.833333	7.0	-2.4	0
##	163		7.2	-1.5	0
##	164		7.1	-1.8	0
##		1474.833333	7.2	-1.5	0
##	166		7.2	-1.5	0
##		1490.866667	7.2	-1.5	0
##	168		7.2	-1.5	0
##	169		6.6	-1.1	0
##	170		6.2	-1.3	0
##	171		6.2	-1.3	0
		1530.833333	6.4	-0.9	0
##	173	1538.850000	5.8	-0.6	0

##	174	1546.866667	6.0	-0.5	0
##	175	1554.833333	6.1	-0.4	0
##	176	1562.866667	5.7	-0.8	0
##	177	1570.833333	5.7	-0.8	0
##	178	1578.833333	3.7	-1.1	0
##	179	1586.850000	1.5	0.9	0
##	180	1594.850000	1.5	0.9	0
##	181	1602.833333	3.0	0.0	0
##	182	1610.850000	3.4	0.5	0
##	183	1618.850000	3.4	0.5	0
##	184	1626.850000	3.3	0.8	0
##	185	1634.850000	3.7	1.0	0
##	186	1642.833333	3.6	1.1	0
##	187	1650.833333	2.5	-0.2	0
##	188	1658.833333	2.4	0.2	0
##	189	1666.833333	2.4	0.2	0
##	190	1674.833333	1.0	1.1	0
##	191	1682.866667	0.9	1.6	0
##	192	1690.833333	1.6	0.8	0
##	193	1698.833333	2.0	0.3	0
##	194	1706.850000	2.4	0.2	0
##	195	1714.850000	2.4	0.2	0
##	196	1722.833333	2.0	-0.1	0
##	197	1730.850000	2.3	0.6	0
##	198	1738.833333	2.3	0.6	0
##	199	1746.850000	1.4	0.1	0
##	200	1754.850000	1.5	0.9	0