## **Untitled**

```
-- Attaching core tidyverse packages ----- tidyverse 2.0.0 --
          1.1.4
v dplyr
                   v readr
                                2.1.5
           1.0.0
v forcats
                                1.5.1
                     v stringr
v ggplot2 3.5.1
                   v tibble 3.2.1
                               1.3.1
v lubridate 1.9.4
                     v tidyr
          1.0.4
v purrr
-- Conflicts ----- tidyverse_conflicts() --
x dplyr::filter() masks stats::filter()
x dplyr::lag()
                 masks stats::lag()
i Use the conflicted package (<a href="http://conflicted.r-lib.org/">http://conflicted.r-lib.org/</a>) to force all conflicts to become
Registered S3 method overwritten by 'mosaic':
  method
                                  from
  fortify.SpatialPolygonsDataFrame ggplot2
The 'mosaic' package masks several functions from core packages in order to add
additional features. The original behavior of these functions should not be affected by this
Attaching package: 'mosaic'
The following object is masked from 'package:Matrix':
   mean
The following objects are masked from 'package:dplyr':
    count, do, tally
The following object is masked from 'package:purrr':
```

cross

```
The following object is masked from 'package:ggplot2':
    stat

The following objects are masked from 'package:stats':
    binom.test, cor, cor.test, cov, fivenum, IQR, median, prop.test, quantile, sd, t.test, var

The following objects are masked from 'package:base':
    max, mean, min, prod, range, sample, sum

Attaching package: 'infer'

The following objects are masked from 'package:mosaic':
    prop_test, t_test
```

## Warm up

**Example:** You are testing seeds from a new plant variety. You plant 10 seeds (n=10) and observe that 3 of them successfully germinate (k=3). Consider two hypotheses about the true germination probability (p) for this variety:

Hypothesis A:

Hypothesis B:

Given you observed 3 germinations out of 10 seeds, which hypothesis (A or B) is more supported by the data?

In general, the *likelihood* of seeing X=3 given p is:

3 ways of finding the maximum:

## 1. Approximate solution graphically

