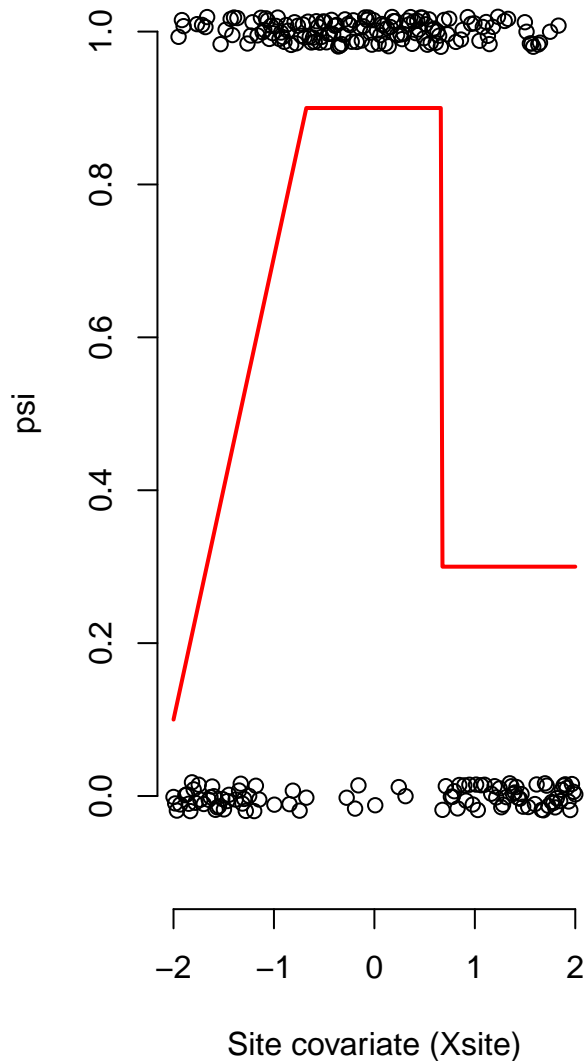


Occupancy probability (red) and realized presence/absence (black circles)



Detection probability (red) and observed data (black circles)

