Package ‘eRTG3D’

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Title Generate Empirically Informed Random Trajectories in 3-D

Version 0.5.3

URL https://github.com/munterfinger/eRTG3D

Description The empirically informed random trajectory generator in three dimensions (eRTG3D) is an algorithm to generate realistic random trajectories in a 3-D space between two given fix points in space. The trajectory generation is based on empirical distribution functions extracted from observed trajectories (training data) and thus reflects the geometrical movement characteristics of the mover.

Depends R (>= 3.5.0)

Imports CircStats (>= 0.2-4), doParallel (>= 1.0.11), ggplot2 (>= 2.2.1), gridExtra (>= 2.3), raster (>= 2.6-7), rasterVis (>= 0.45), parallel (>= 3.5.0), pbmcapply (>= 1.2.5), plyr (>= 1.8.4), plotly (>= 4.7.1), sp (>= 1.3-1)

License GPL (>=3)

Encoding UTF-8

LazyData true

RoxygenNote 6.0.1

Suggests knitr (>= 1.20), rmarkdown (>= 1.10), sf (>= 0.6-3)

VignetteBuilder knitr

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R topics documented:

`chiMaps` *Chi maps of two variables*

Description

Calculates the chi maps for one `rasterStack` or all raster all the raster pairs stored in two `rasterStack`s. As observed values, the first stack is used. The expected value is either set to the mean of the first stack, or if given to be the values of the second stack.

Usage

```
chiMaps(stack1, stack2 = NULL)
```

Arguments

`stack1`	`rasterStack`
`stack2`	`rasterStack` `NULL` or containing the same number of `rasterLayers` and has euqal extent and resolution.

Value

A `rasterStack` containing the chi maps.

Examples

```
chiMaps(stack1)
```

`dem` *Example digital elevation model (DEM)*

Description

This is data to be included in the package and can be used to test its functionality. The `dem` data is a `RasterLayer` and has a resolution of 90 meters. It is the topography of the Swiss midlands. The complete dataset can be downloaded directly from www.cgiar-csi.org.

References

http://www.cgiar-csi.org/data/srtm-90m-digital-elevation-database-v4-1

`dem2track.extent` *Crops the DEM to the extent of the track with a buffer*

Description

Crops the DEM to the extent of the track with a buffer

Usage

```
dem2track.extent(DEM, track, buffer = 100)
```

Arguments

`DEM`	a raster containing a digital elevation model, covering the extent as the track
`track`	data.frame with x,y,z coordinates of the original track
`buffer`	buffer with, by default set to 100

Value

A the cropped digital elevation model as a raster layer.

Examples

```
dem2track.extent(DEM, track)
```

dist2point.3d *Distance of each track point to a given point*

Description

Distance of each track point to a given point

Usage

```
dist2point.3d(track, point, groundDistance = FALSE)
```

Arguments

track	a list containing data.frames with x,y,z coordinates or a data.frame
point	a vector with x, y or x, y, z coordinates
groundDistance	logical: calculate only ground distance in x-y plane?

Value

Returns the distance of each track point to the point.

Examples

```
dist3point.3d(track, point)
```

dist2target.3d *Distance to target*

Description

Calculates the distance between every point in the track and the last point (target).

Usage

```
dist2target.3d(track)
```

Arguments

track	a track data.frame containing x, y and z coordinates

Value

A numeric vector with the distances to target

Examples

```
dist2target.3d(track)
```

`filter.dead.ends` *Remove dead ends*

Description

Function to filter out tracks that have found a dead end

Usage

```
filter.dead.ends(cerwList)
```

Arguments

`cerwList`	list of data.frames and NULL entries

Value

A list that is only containing valid tracks.

Examples

```
filter.dead.ends(cerwList)
```

`get.densities.3d` *Extract tldCube and autodifferences functions*

Description

Creates a list consisting of the 3 dimensional probability distribution cube for turning angle, lift angle and step length (turnLiftStepHist) as well as the uni-dimensional distributions of the differences of the turn angles, lift angles and step lengths with a lag of 1 to maintain minimal level of autocorrelation in each of the terms. Additionally also the distribution of the flight height over the ellipsoid (absolute) and the distribution of flight height over the topography (relative) can be included.

Usage

```
get.densities.3d(turnAngle, liftAngle, stepLength, deltaLift, deltaTurn,
  deltaStep, gradientAngle = NULL, heightEllipsoid = NULL,
  heightTopo = NULL, maxBin = 25)
```

Arguments

`turnAngle`	turn angles of the track (t)
`liftAngle`	lift angles of the track (l)
`stepLength`	stepLength of the track (d)
`deltaLift`	auto differences of the turn angles (diff(t))
`deltaTurn`	auto differences of the lift angles (diff(l))
`deltaStep`	auto differences of the step length (diff(d))

`gradientAngle` `NULL` or the gardient angles of the track

`heightEllipsoid`
flight height over the ellipsoid (absolute) or `NULL` to exclude this distribution

`heightTopo` flight height over the topography (relative) or `NULL` to exclude this distribution

`maxBin` numeric scalar, maximum number of bins per dimension of the tld-cube (turnLiftStepHist)

Value

A list containing the tldCube and the autodifferences functions (and additionally the flight height distribution functions)

Examples

```
get.densities.3d(track, heightDist = TRUE)
```

`get.glideRatio.3d` *Glide ratio*

Description

Calculates the ratio between horizontal movement and vertical movement. The value expresses the distance covered forward movement per distance movement in sinking.

Usage

```
get.glideRatio.3d(track)
```

Arguments

`track` a track data.frame containing x, y and z coordinates of a gliding section

Value

The ratio between horizontal and vertical movement.

Examples

```
get.glideRatio.3d(track)
```

`get.section.densities.3d` *Extract tldCube and autodifferences functions from track sections*

Description

Creates a list consisting of the 3 dimensional probability distribution cube for turning angle, lift angle and step length (turnLiftStepHist) as well as the uni-dimensional distributions of the differences of the turning angles, lift angles and step lengths with a lag of 1 to maintain minimal level of autocorrelation in each of the terms.

Usage

```
get.section.densities.3d(trackSections, gradientDensity = TRUE,
  heightDistEllipsoid = TRUE, DEM = NULL, maxBin = 25)
```

Arguments

`trackSections`	list of track sections got by the track.split.3d function
`gradientDensity`	logical: Should a distribution of the gradient angle be extracted and later used in the simulations?
`heightDistEllipsoid`	logical: Should a distribution of the flight height over ellipsoid be extracted and later used in the sim.cond.3d()?
`DEM`	a raster containing a digital elevation model, covering the same extent as the track sections
`maxBin`	numeric scalar, maximum number of bins per dimension of the tld-cube (turnLiftStepHist)

Value

A list containing the tldCube and the autodifferences functions (and additionally the height distribution function)

Examples

```
get.section.densities.3d(trackSections)
```

`get.track.densities.3d` *Extract tldCube and autodifferences functions from a consistent track*

Description

Get densities creates a list consisting of the 3 dimensional probability distribution cube for turning angle, lift angle and step length (turnLiftStepHist) as well as the uni-dimensional distributions of the differences of the turning angles, lift angles and step lengths with a lag of 1 to maintain minimal level of autocorrelation in each of the terms.

Usage

```
get.track.densities.3d(track, gradientDensity = TRUE,
  heightDistEllipsoid = TRUE, DEM = NULL, maxBin = 25)
```

Arguments

`track` a data.frame with 3 columns containing the x,y,z coordinates

`gradientDensity`
logical: Should a distribution of the gradient angle be extracted and later used in the simulations?

`heightDistEllipsoid`
logical: Should a distribution of the flight height over ellipsoid be extracted and later used in the sim.cond.3d()?

`DEM` a raster containing a digital elevation model, covering the same extent as the track

`maxBin` numeric scalar, maximum number of bins per dimension of the tld-cube (turnLiftStepHist)

Value

A list containing the tldCube and the autodifferences functions (and additionally the height distribution function)

Note

The time between the acquisition of fix points of the track must be constant, otherwise this leads to distorted statistic distributions, which increases the probability of dead ends. In this case please check track.split.3d and get.section.densities.3d

Examples

```
get.track.densities.3d(track, heightDist = TRUE)
```

---

is.sf.3d — *Tests if the object is a simple feature collection (class: 'sf, data.frame')*

Description

Tests if the object is a simple feature collection (class: `'sf, data.frame'`)

Usage

```
is.sf.3d(track)
```

Arguments

`track` any object to test

Value

A logical: `TRUE` if is a simple feature collection (class: `'sf, data.frame'`) of the sf package, `FALSE` otherwise.

Examples

```
is.sf.3d(track)
```

`lift2target.3d` *Lift angle to target*

Description

Calculates the lift angle between every point in the track and the last point (target).

Usage

```
lift2target.3d(track)
```

Arguments

`track`	a track data.frame containing x, y and z coordinates

Value

A numeric vector with the lift angles to target

Examples

```
lift2target.3d(track)
```

`logRasterStack` *Converts a rasterStack to logarithmic scale*

Description

Avoids the problem of -Inf occuring for log(0).

Usage

```
logRasterStack(rStack, standartize = FALSE, InfVal = NA)
```

Arguments

`rStack`	rasterStack to convert to logarithmic scale
`standartize`	logical: standartize cube between 0 and 1
`InfVal`	the value that `Inf` and `-Inf` should be rpeplaced with

Value

A rasterStack in logarithmic scale

Examples

```
logRasterStack(rStack)
```

---

movingMedian *Moving median in one dimension*

Description

Applies a twosided moving median window on a vector, where the window paramter is the total size of the window. The value in the window middle is the index where the median of the window is written. Therefore the window size has to be an uneven number. The border region of the vetor is filled with a one-sided median. There might be border effects.

Usage

```
movingMedian(data, window)
```

Arguments

`data`	numeric vector
`window`	uneven number for the size of the moving window

Value

A numeric vector.

Examples

```
movingMedian(data, window = 5)
```

---

n.sim.cond.3d *Conditional Empirical Random Walks (CERW) in 3-D*

Description

Creates n conditional empirical random walks, with a specific starting and ending point, geometrically similar to the initial trajectory by applying sim.cond.3d multiple times.

Usage

```
n.sim.cond.3d(n.sim, n.locs, start = c(0, 0, 0), end = start, a0, g0,
  densities, qProbs, error = FALSE, multicore = FALSE, DEM = NULL,
  BG = NULL)
```

Arguments

`n.sim`	number of CERWs to simulate
`n.locs`	length of the trajectory in locations
`start`	numeric vector of length 3 with the coordinates of the start point
`end`	numeric vector of length 3 with the coordinates of the end point
`a0`	initial incoming heading in radian
`g0`	initial incoming gradient/polar angle in radian
`densities`	list object returned by the get.densities.3d function
`qProbs`	list object returned by the qProb.3d function
`error`	logical: add random noise to the turn angle, lift angle and step length to account for errors measurements?
`multicore`	logical: run computations in parallel (n-1 cores)?
`DEM`	raster layer containing a digital elevation model, covering the area between start and end point
`BG`	a background raster layer that can be used to inform the choice of steps

Value

A list containing the CERWs or `NULL`s if dead ends have been encountered.

Examples

```
n.sim.cond.3d(n.sim, n.locs, start = c(0,0,0), end=start, a0, g0, densities, qProbs)
```

`n.sim.glidingSoaring.3d`

Simulates multiple 'gliding & soaring' tracks with a given number of gliding steps

---

Description

Creates conditional empirical random walks in gliding mode, between a start and end point. The walk is performed on a MODE layer and, if provided, additionally on a background and digital elevation layer. The gliding is simulated with sim.cond.3d and soaring with sim.uncond.3d, therefore soaring is not restricted towards the target and can happen completly free as long as there are good thermal conditions. It is important to extract for every mode in the MODE raster layer a corresponding densities object with get.densities.3d and pass them to the function.

Usage

```
n.sim.glidingSoaring.3d(n.sim = 1, multicore = FALSE, MODE, dGliding,
  dSoaring, qGliding, start = c(0, 0, 0), end = start, a0, g0,
  error = TRUE, smoothTransition = TRUE, glideRatio = 20, DEM = NULL,
  BG = NULL)
```

Arguments

`n.sim`	number of simulations to produce
`multicore`	logical: should simulations be spread to the available number of cores?
`MODE`	raster layer containing the number/index of the mode, which should be used at each location
`dGliding`	density object returned by the get.densities.3d function for gliding mode
`dSoaring`	density object returned by the get.densities.3d function for soaring mode
`qGliding`	the Q probabilites for the steps in gliding mode (qProb.3d)
`start`	numeric vector of length 3 with the coordinates of the start point
`end`	numeric vector of length 3 with the coordinates of the end point
`a0`	initial incoming heading in radian
`g0`	initial incoming gradient/polar angle in radian
`error`	logical: add random noise to the turn angle, lift angle and step length to account for errors measurements?
`smoothTransition`	logical: should the transitions between soaring and the following gliding sections be smoothed? Recommended to avoid dead ends
`glideRatio`	ratio between vertical and horizontal movement, by default set to 15 meters forward movement per meter vertical movement
`DEM`	raster layer containing a digital elevation model, covering the area between start and end point
`BG`	a background raster layer that can be used to inform the choice of steps

Value

A list containing 'soaring-gliding' trajectories or `NULL`s if dead ends have been encountered.

Note

The MODE raster layer must be in the following structure: Gliding pixels have the value 1 and soaring pixel the values 2. `NA`'s are not allowed in the raster.

Examples

```
n.sim.glidingSoaring.3d(locsVec, start = c(0,0,0), end=start, a0, g0, dList, qList, MODE)
```

`niclas` *Example track data.frame*

Description

This is data to be included in the package and can be used to test its functionality. The track consists of x, y and z coordinates and represents the movement of a stork called `niclas` in the Swiss midlands.

References

https://www.movebank.org

plot2d *Plot function to plot the 3-D tracks in 2-D plane*

Description

Plot function to plot the 3-D tracks in 2-D plane

Usage

```
plot2d(origTrack, simTrack = NULL, titleText = character(1), DEM = NULL,
  BG = NULL, padding = 0.1, alpha = 0.7, resolution = 500)
```

Arguments

origTrack	a list containing data.frames with x,y,z coordinates or a data.frame
simTrack	a list containing data.frames with x,y,z coordinates or a data.frame
titleText	string with title of the plot
DEM	an object of type RasterLayer, needs overlapping extent with the line(s)
BG	an object of type RasterLayer, needs overlapping extent with the line(s)
padding	adds a pad to the 2-D space in percentage (by default set to 0.1)
alpha	a number between 0 and 1, to specify the transparency of the simulated line(s)
resolution	number of pixels the rasters are downsampled to (by default set to 500 pixels)

Value

A ggplot2 object.

Examples

```
plot3d(track)
```

plot3d *Plot track(s) with a surface of a digital elevation model in three dimensions*

Description

Plot track(s) with a surface of a digital elevation model in three dimensions

Usage

```
plot3d(origTrack, simTrack = NULL, titleText = character(1), DEM = NULL,
  padding = 0.1, timesHeight = 10)
```

Arguments

`origTrack`	a list containing data.frames with x,y,z coordinates or a data.frame
`simTrack`	a list containing data.frames with x,y,z coordinates or a data.frame
`titleText`	string with title of the plot
`DEM`	an object of type `RasterLayer`, needs overlapping extent with the line(s)
`padding`	adds a pad to the 2-D space in percentage (by default set to 0.1)
`timesHeight`	multiply the height scale by a scalar (by default set to 10)

Value

Plots a plotly object

Examples

```
plot3d(track)
```

`plot3d.densities` *Density plots of turn angle, lift angle and step length*

Description

The function takes either one track or two tracks. The second track can be a list of tracks (eg. the output of n.sim.cond.3d), Then the densities of turn angle, lift angle and step length of all the simulations is taken. Additionally the autodifferences parameter can be set to true, then the densities of the autodifferences in turn angle, lift angle and step length are visualized.

Usage

```
plot3d.densities(track1, track2 = NULL, autodifferences = FALSE,
  scaleDensities = FALSE)
```

Arguments

`track1`	a list containing a data.frame with x,y,z coordinates or a data.frame
`track2`	a list containing a data.frame with x,y,z coordinates or a data.frame
`autodifferences`	logical: should the densities of the autodifferences in turn angle, lift angle and step length are visualized.
`scaleDensities`	logical: should densities be scaled between 0 and 1, then sum of the area under the curve is not 1 anymore!

Value

A ggplot2 object.

Examples

```
plot3d.densities(track)
```

`plot3d.multiplot` *Multiple plot function for ggplot objects*

Description

If the layout is something like `matrix(c(1,2,3,3), nrow=2, byrow=TRUE)`, then plot 1 will go in the upper left, 2 will go in the upper right, and 3 will go all the way across the bottom.

Usage

```
plot3d.multiplot(..., plotlist = NULL, cols = 1, layout = NULL)
```

Arguments

`...`	ggplot objects
`plotlist`	a list of ggplot objects
`cols`	number of columns in layout
`layout`	a matrix specifying the layout. If present, `cols` is ignored.

Value

Nothing, plots the ggplot2 objects.

Examples

```
plot3d.multiplot(p1, p2, p3)
```

`plot3d.tldCube` *Visualize turn-lift-step histogram*

Description

Creates a three dimensional scatterplot of the possibles next steps, based on the tldCube, which was extracted from a track.

Usage

```
plot3d.tldCube(tldCube)
```

Arguments

`tldCube`	tldCube; the ouptut from turnLiftStepHist or get.densities.3d

Value

Plots a plotly object

Examples

```
plot3d.tldCube(D$tldCube)
```

plotRaster — *Plots a rasterLayer or rasterStack*

Description

Plots a rasterLayer or rasterStack

Usage

```
plotRaster(r, title = character(0), centerColorBar = FALSE, ncol = NULL)
```

Arguments

`r`	`rasterLayer` or `rasterStack`
`title`	title text of plot(s)
`centerColorBar`	logical: center colobar around 0 and use `RdBuTheme()`?
`centerColorBar`	number of columns to plot a stack, by default estimated by the square root

Value

Plots the rasters

Examples

```
plotRaster(r)
```

qProb.3d — *Q probabilities for n steps*

Description

Calculates the Q probability, representing the pull to the target. The number of steps on which the Q prob will be quantified is number of total segments less than one (the last step is defined by the target itself).

Usage

```
qProb.3d(sim, n.locs, multicore = FALSE, maxBin = 25)
```

Arguments

`sim`	the result of sim.uncond.3d, or a data frame with at least x,y,z-coordinates, the arrival azimuth and the arrival gradient.
`n.locs`	number of total segments to be modeled, the length of the desired conditional empirical random walk
`multicore`	logical: run computations in parallel (n-1 cores)?
`maxBin`	numeric scalar, maximum number of bins per dimension of the tld-cube (turnLiftStepHist)

Value

A list containing the Q - tldCubes for every step

Examples

```
qProb.3d(sim, n.locs)
```

`reproduce.track.3d` *Reproduce a track with the eRTG3D*

Description

Simulates n tracks with the geometrical properties of the original track, between the same start and end point.

Usage

```
reproduce.track.3d(track, n.sim = 1, multicore = FALSE, error = TRUE,
  DEM = NULL, BG = NULL, filterDeadEnds = TRUE, plot2d = FALSE,
  plot3d = FALSE, maxBin = 25, gradientDensity = TRUE)
```

Arguments

`track`	data.frame with x,y,z coordinates of the original track
`n.sim`	number of simulations that should be done
`multicore`	logical: run calculations on multiple cores?
`error`	logical: add error term to movement in simulation?
`DEM`	a raster containing a digital elevation model, covering the same extent as the track
`BG`	a raster influencing the probabilities.
`filterDeadEnds`	logical: Remove tracks that ended in a dead end?
`plot2d`	logical: plot tracks on 2-D plane?
`plot3d`	logical: plot tracks in 3-D?
`maxBin`	numeric scalar, maximum number of bins per dimension of the tld-cube (turnLiftStepHist)
`gradientDensity`	logical: Should a distribution of the gradient angle be extracted and used in the simulations (get.densities.3d)?

Value

A list or data.frame containing the simulated track(s) (CERW).

Examples

```
reproduce.track.3d(track)
```

saveImageSlices *Export a dataCube as image slice sequence*

Description

Exports a dataCube of type `rasterStack` as Tiff image sequence. Image sequnces are a common structre to represent voxel data and most of the specific software to visualize voxel data is able to read it (e.g. blender)

Usage

```
saveImageSlices(rStack, filename, dir = getwd(), NaVal = 0)
```

Arguments

`rStack`	rasterStack to be saved to Tiff image slices
`filename`	name of the image slices
`dir`	directory, where the slices should be stored
`NaVal`	numeric value that should represent NA values in the Tiff image, default is `NaVal = 0`

Value

Saves the Tiff image files.

Examples

```
saveImageSlices(rstack, filename = "image")
```

sf2df.3d *Converts a sf data.frame to a normal dataframe*

Description

Converts a sf data.frame to a normal dataframe

Usage

```
sf2df.3d(track)
```

Arguments

`track`	An object of type `'sf, data.frame'`

Value

A data.frame.

Examples

```
sf2df.3d(df)
```

`sim.cond.3d` *Conditional Empirical Random Walk (CERW) in 3-D*

Description

Creates a conditional empirical random walk, with a specific starting and ending point, geometrically similar to the initial trajectory (extractMethod: raster overlay method can take "simple" or "bilinear")

Usage

```
sim.cond.3d(n.locs, start = c(0, 0, 0), end = start, a0, g0, densities,
  qProbs, error = FALSE, DEM = NULL, BG = NULL)
```

Arguments

`n.locs`	length of the trajectory in locations
`start`	numeric vector of length 3 with the coordinates of the start point
`end`	numeric vector of length 3 with the coordinates of the end point
`a0`	initial incoming heading in radian
`g0`	initial incoming gradient/polar angle in radian
`densities`	list object returned by the get.densities.3d function
`qProbs`	list object returned by the qProb.3d function
`error`	logical: add random noise to the turn angle, lift angle and step length to account for errors measurements?
`DEM`	raster layer containing a digital elevation model, covering the area between start and end point
`BG`	a background raster layer that can be used to inform the choice of steps

Value

A trajectory in the form of data.frame

Examples

```
sim.cond.3d(n.locs, start, end=start, a0, g0, densities, qProbs)
```

sim.crw.3d — *Simulation of a three dimensional Correlated Random Walk*

Description

Simulation of a three dimensional Correlated Random Walk

Usage

```
sim.crw.3d(nStep, rTurn, rLift, meanStep, start = c(0, 0, 0))
```

Arguments

`nStep`	the number of steps of the simulated trajectory
`rTurn`	the correlation on the turn angle
`rLift`	the correlation of the lift angle
`meanStep`	the mean step length
`start`	a vector of length 3 containing the coordinates of the start point of the trajectory

Value

A trajectory in the form of data.frame

Examples

```
sim.crw.3d(nStep, rTurn, rLift, meanStep, start = c(0,0,0))
```

sim.glidingSoaring.3d — *Simulates 'gliding & soaring' track with a given number of gliding steps*

Description

Creates a conditional empirical random walk in gliding mode, between a start and end point. The walk is performed on a MODE layer and, if provided, additionally on a background and digital elevation layer. The gliding is simulated with sim.cond.3d and soaring with sim.uncond.3d, therefore soaring is not restricted towards the target and can happen completly free as long as there are good thermal conditions. It is important to extract for every mode in the MODE raster layer a corresponding densities object with get.densities.3d and pass them to the function.

Usage

```
sim.glidingSoaring.3d(MODE, dGliding, dSoaring, qGliding, start = c(0, 0, 0),
  end = start, a0, g0, error = TRUE, smoothTransition = TRUE,
  glideRatio = 15, DEM = NULL, BG = NULL)
```

Arguments

`MODE`	raster layer containing the number/index of the mode, which should be used at each location
`dGliding`	density object returned by the get.densities.3d function for gliding mode
`dSoaring`	density object returned by the get.densities.3d function for soaring mode
`qGliding`	the Q probabilites for the steps in gliding mode (qProb.3d)
`start`	numeric vector of length 3 with the coordinates of the start point
`end`	numeric vector of length 3 with the coordinates of the end point
`a0`	initial incoming heading in radian
`g0`	initial incoming gradient/polar angle in radian
`error`	logical: add random noise to the turn angle, lift angle and step length to account for errors measurements?
`smoothTransition`	logical: should the transitions between soaring and the following gliding sections be smoothed? Recommended to avoid dead ends
`glideRatio`	ratio between vertical and horizontal movement, by default set to 15 meters forward movement per meter vertical movement
`DEM`	raster layer containing a digital elevation model, covering the area between start and end point
`BG`	a background raster layer that can be used to inform the choice of steps

Value

A 'soaring-gliding' trajectory in the form of data.frame

Note

The MODE raster layer must be in the following structure: Gliding pixels have the value 1 and soaring pixel the values 2. `NA`'s are not allowed in the raster.

Examples

```
sim.glidingSoaring.3d(locsVec, start = c(0,0,0), end=start, a0, g0, dList, qList, MODE)
```

`sim.uncond.3d` *Unconditional Empirical Random Walk (UERW) in 3-D*

Description

This function creates unconditional walks with prescribed empirical properties (turning angle, lift angle and step length and the auto-differences of them. It can be used for uncon- ditional walks or to seed the conditional walks with comparably long simulations. The conditional walk connecting a given start with a certain end point by a given number of steps needs an attraction term (the Q probability, see qProb.3d) to ensure that the target is approached and hit. In order to calculate the Q probability for each step the distribution of turns and lifts to target and the distribution of distance to target has to be known. They can be derived from the empirical data (ideally), or estimated from an unconditional process with the same properties. Creates a unconditional empirical random walk, with a specific starting point, geometrically similar to the initial trajectory.

Usage

```
sim.uncond.3d(n.locs, start = c(0, 0, 0), a0, g0, densities, error = TRUE)
```

Arguments

`n.locs`	the number of locations for the simulated track
`start`	vector indicating the start point `c(x,y,z)`
`a0`	initial heading in radian
`g0`	initial gradient/polar angle in radian
`densities`	list object returned by the get.densities.3d function
`error`	logical: add random noise to the turn angle, lift angle and step length to account for errors measurements?

Value

A 3 dimensional trajectory in the form of a data.frame

Note

Simulations connecting start and end points with more steps than 1/10th or more of the number of steps of the empirical data should rather rely on simulated unconditional walks with the same properties than on the empirical data (`factor = 1500`).

Random initial heading

For a random initial heading a0 use: `sample(atan2(diff(coordinates(track)[,2]), diff(coordinates(track)[`

Examples

```
sim.uncond.3d(n.locs, start=c(0,0,0), a0, g0, densities)
```

`test.eRTG.3d` *Test the functionality of the eRTG3D*

Description

The test simulates a CRW with given parameters and reconstructs it by using the eRTG3D

Usage

```
test.eRTG.3d(multicore = FALSE, returnResult = FALSE, plot2d = FALSE,
  plot3d = TRUE, plotDensities = TRUE)
```

Arguments

`multicore`	logical: test with multicore?
`returnResult`	logical: return tracks generated?
`plot2d`	logical: plot tracks on 2-D plane?
`plot3d`	logical: plot tracks in 3-D?
`plot3d`	logical: plot densities of turning angle, lift angle and step length?

Value

A list containing the original CRW and the simulated track (CERW).

Examples

```
test.eRTG3D.3d()
```

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test.verification.3d *Statistical Verification of the simulated track*

Description

Uses two-sample Kolmogorov-Smirnov test or the one-sample t-test to compare the geometric characteristics of the original track with the characteristics of the simulated track.

Usage

```
test.verification.3d(track1, track2, alpha = 0.05, plot = FALSE,
  test = "ks")
```

Arguments

`track1`	data.frame or list of data.frames with x,y,z coordinates of the original track
`track2`	data.frame or list of data.frames with x,y,z coordinates of the simulated track
`alpha`	scalar: significance level, default `alpha = 0.05`
`plot`	logical: plot the densities or differences of turn angle, lift angle and step length of the two tracks?
`test`	character: either `"ks"` or `"ttest"` to choose the kind of test procedure.

Value

Test objects of the 6 two-sample Kolmogorov-Smirnov test conducted.

Note

By choosing `test = "ttest"` a random sample, without replacement is taken from the longer track, to shorten it to the length of the longer track. The order of the shorter track is also sampled randomly. Then the two randomly ordered vectors of turn angles, lift angles and step lengths are substracted from each other. If the both tracks stem from the same distributions the the mean deviatio should tend to towards zero, therefore the difference is tested two-sided against `mu = 0` with a one-sample t-test.

By setting `test = "ks"` a two-sample Kolmogorov-Smirnov test is carried out on the distributions of turn angles, lift angles and step lengths of the two tracks.

Examples

```
test.verification.3d(track1, track2)
```

track.extent — *Extent of track(s)*

Description

Extent of track(s)

Usage

```
track.extent(track, zAxis = FALSE)
```

Arguments

`track`	a list containing data.frames with x,y,z coordinates or a data.frame
`zAxis`	logical: return also the extent of the Z axis?

Value

Returns an extent object of the raster package in the 2–D case and a vector in the 3–D case.

Examples

```
track.extent(track, zAxis = TRUE)
```

track.properties.3d — *Track properties of a 3-D track*

Description

Returns the properties (distances, azimuth, polar angle, turn angle & lift angle) of a track in three dimensions.

Usage

```
track.properties.3d(track)
```

Arguments

`track`	data.frame with x,y,z coordinates

Value

The data.frame with track properties

Examples

```
track.properties.3d(track)
```

`track.split.3d` *This function splits the by outliers in the time lag.*

Description

The length of timeLag must be the the track's length minus 1 and represents the time passed between the fix point acquisition

Usage

```
track.split.3d(track, timeLag, lag = NULL, tolerance = NULL)
```

Arguments

`track`	track data.frame with x, y and z coordinates
`timeLag`	a numeric vector with the time passed between the fix point acquisition
`lag`	NULL or a manually chosen lag
`tolerance`	NULL or a manually chosen tolerance

Value

A list containing the splitted tracks.

Examples

```
track.split.3d(track, timeLag)
```

`track2sf.3d` *Converts a track to a* `'sf, data.frame'`

Description

Converts a track to a `'sf, data.frame'`

Usage

```
track2sf.3d(track, CRS = NA)
```

Arguments

`track`	eRTG3D track data.frame or a matrix
`CRS`	string containing the proj4 code of the CRS

Value

A track of type `'sf, data.frame'`.

Examples

```
track2sf.3d(track, "+proj=longlat +ellps=WGS84 +datum=WGS84 +no_defs")
```

transformCRS.3d *Transform coordinates reference system of a 3-D track*

Description

Attention: Please use this function for CRS transformations, because it is based on the st_transform from the sf package. Therefore is supports CRS transformations in 3-D. Note: spTransform from the sp package only supports transformations in the 2D plane, which will cause distortions in the third dimension.

Usage

```
transformCRS.3d(track, fromCRS, toCRS)
```

Arguments

`track`	data.frame with x,y,z coordinates
`fromCRS`	string: proj4 of current CRS
`toCRS`	string: proj4 of CRS to be converted in

Value

A data.frame containing x,y,z and variables.

Examples

```
transformCRS.3d(track, fromCRS="+init=epsg:4326", toCRS="+init=epsg:2056")
```

turn2target.3d *Turn angle to target*

Description

Calculates the turn angle between every point in the track and the last point (target).

Usage

```
turn2target.3d(track)
```

Arguments

`track`	a track data.frame containing x, y and z coordinates

Value

A numeric vector with the turn angles to target

Examples

```
turn2target.3d(track)
```

`turnLiftStepHist` *3 dimensional histogram*

Description

Derives a 3 dimensional distribution of a turn angle, lift angle and step length, using the Freedman–Diaconis rule for estimating the number of bins.

Usage

```
turnLiftStepHist(turn, lift, step, printDims = TRUE, rm.zeros = TRUE,
  maxBin = 25)
```

Arguments

`turn`	numeric vector of turn angles
`lift`	numeric vector of lift angles
`step`	numeric vector of step lengths
`printDims`	logical: should dimensions of tld-Cube be messaged?
`rm.zeros`	logical: should combinations with zero probability be removed?
`maxBin`	numeric scalar, maximum number of bins per dimension of the tld-cube.

Value

A 3 dimensional histogram as data.frame

Examples

```
turnLiftStepHist(turn, lift, step)
```

`voxelCount` *Apply voxel counting on a point cloud*

Description

A `rasterStack` object is created, representing the 3–D voxel cube. The z axis is sliced into regular sections between the maximum and minimum value. For every height slice a raster with points per cell counts is created. Additionally the voxels can be standartized between 0 and 1.

Usage

```
voxelCount(points, extent, xyRes, zRes = xyRes, zMin, zMax,
  standartize = FALSE)
```

Arguments

`points`	a x, y, z data.frame
`extent`	a raster extent object of the extent to create the rasters
`xyRes`	resolution in the ground plane of the created rasters
`zRes`	resolution in the z axis (by default `zRes = xyRes`)
`zMin`	minimum z value
`zMax`	maximum height value
`standartize`	logical: standartize the values?

Value

A `rasterStack` object, representing the 3–D voxel cube.

Examples

```
voxelCount(points, extent, xyRes, zRes = xyRes, zMin, zMax, standartize = FALSE)
```

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