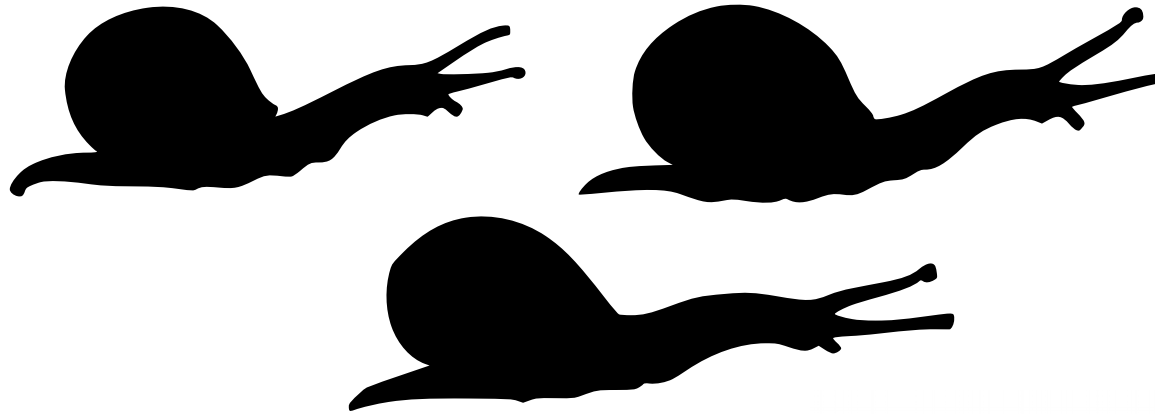


# DISTANCE SAMPLING AND ANIMAL MOVEMENT



Richard Glennie  
University of St Andrews  
rg374@st-andrews.ac.uk



University of  
St Andrews



**CREEM**

Centre for Research into Ecological  
and Environmental Modelling

**Assumption:** Objects are detected at their *initial* location.

**Assume:** Objects are detected at their *initial* location.

**Assume:** Objects are detected at their *initial* location.

**Violate:** Move in response to observer.



**A**ssume: Objects are detected at their *initial* location.

**V**iolate: Move in response to observer.

**M**itigate:

- ✓ Survey Protocol
- ✓ Left truncation
- ✓ Double Observer Methods



**A**ssume: Objects are detected at their *initial* location.

**V**iolate: Move in response to observer.

**M**itigate:

- ✓ Survey Protocol
- ✓ Left truncation
- ✓ Double Observer Methods

Buckland, S.T., Rexstad, E.A., Marques, T.A. and Oedekoven, C.S., 2015. *Distance sampling: methods and applications*. New York, NY, USA: Springer.

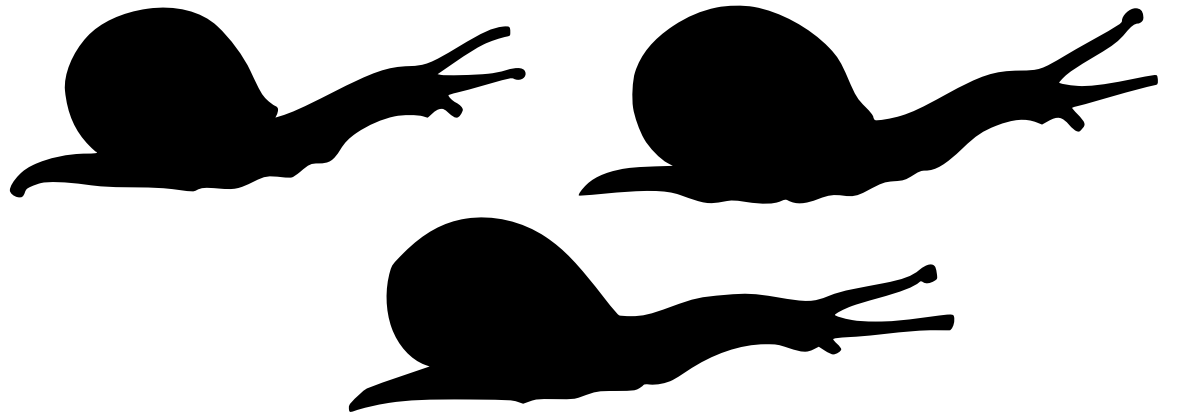
Conn, P.B. and Alisauskas, R.T., 2018. Simultaneous modelling of movement, measurement error, and observer dependence in mark-recapture distance sampling: An application to Arctic bird surveys. *The Annals of Applied Statistics*, 12(1), pp.96-122.

**A**ssume: Objects are detected at their *initial* location.

**V**iolate: Move independently of the observer.

**A**ssume: Objects are detected at their *initial* location.

**V**iolate: Move independently of the observer.

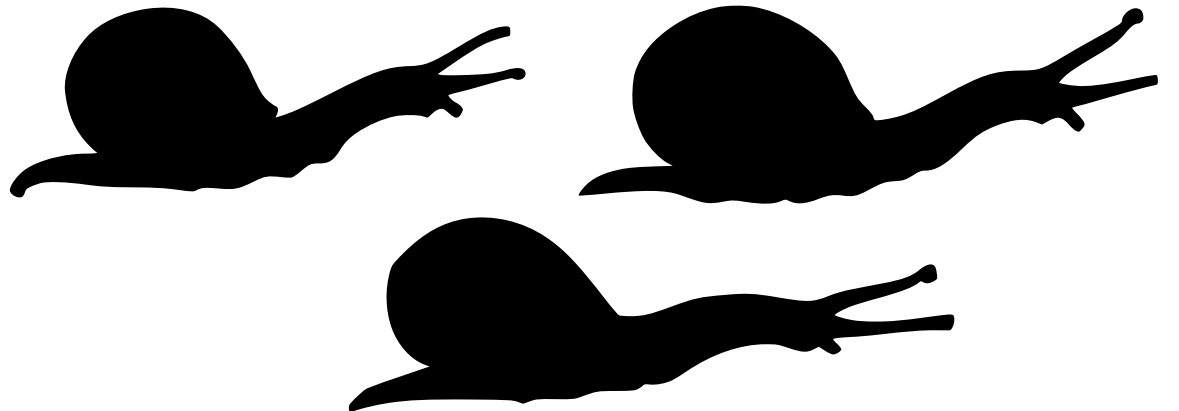




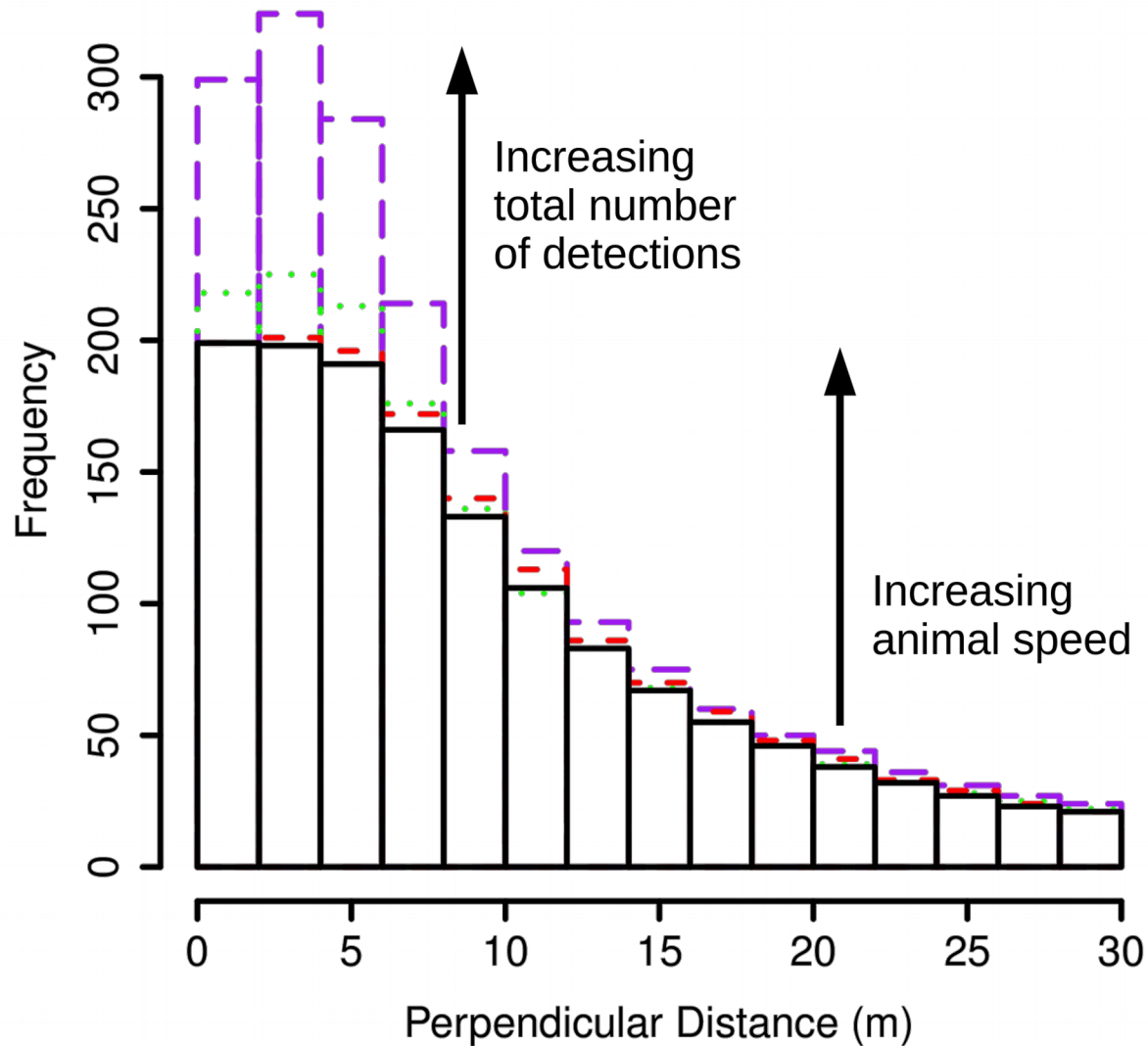
**Assume:** Objects are detected at their *initial* location.

**Violate:** Move independently of the observer.

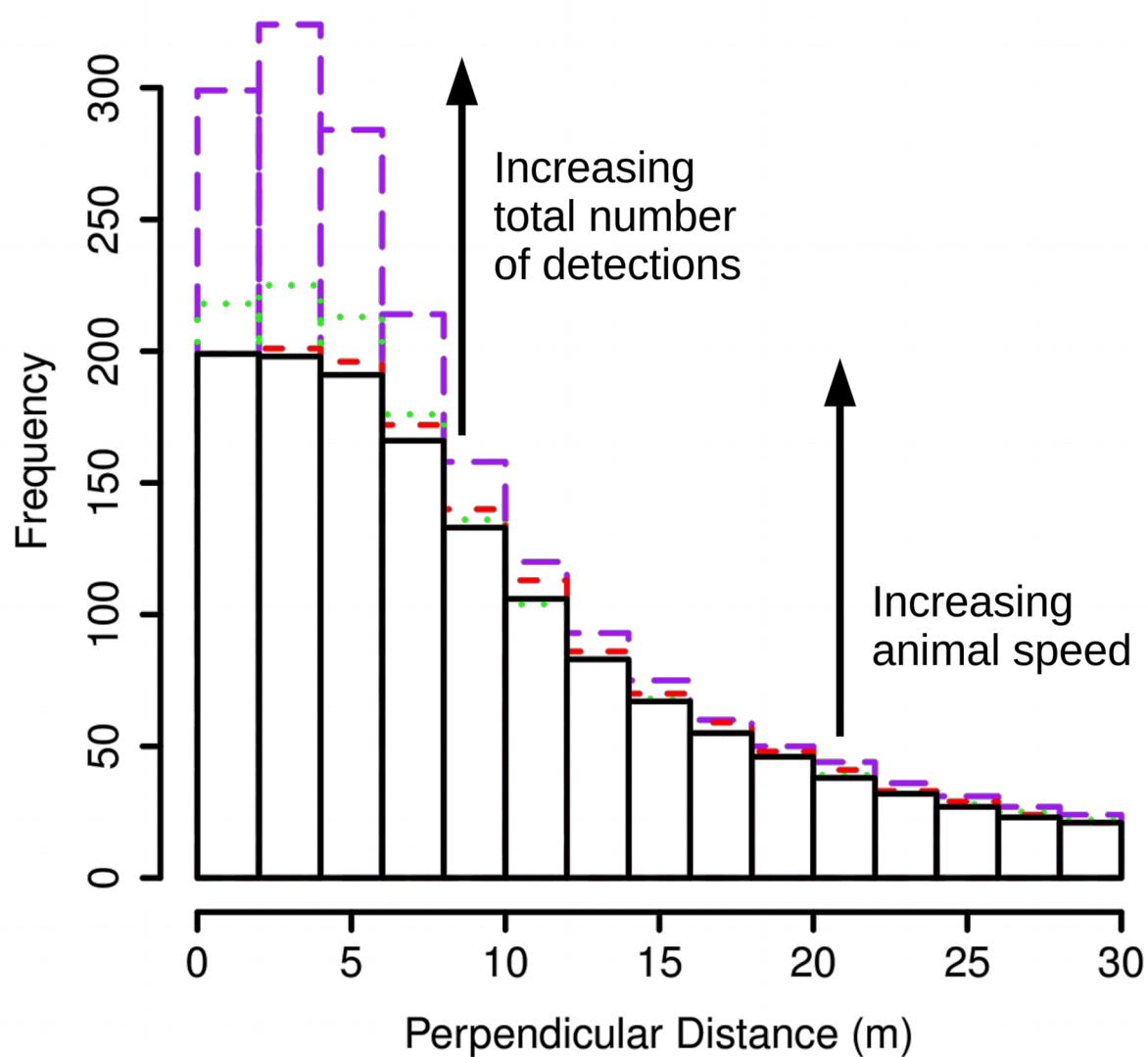
**Mitigate:** ?



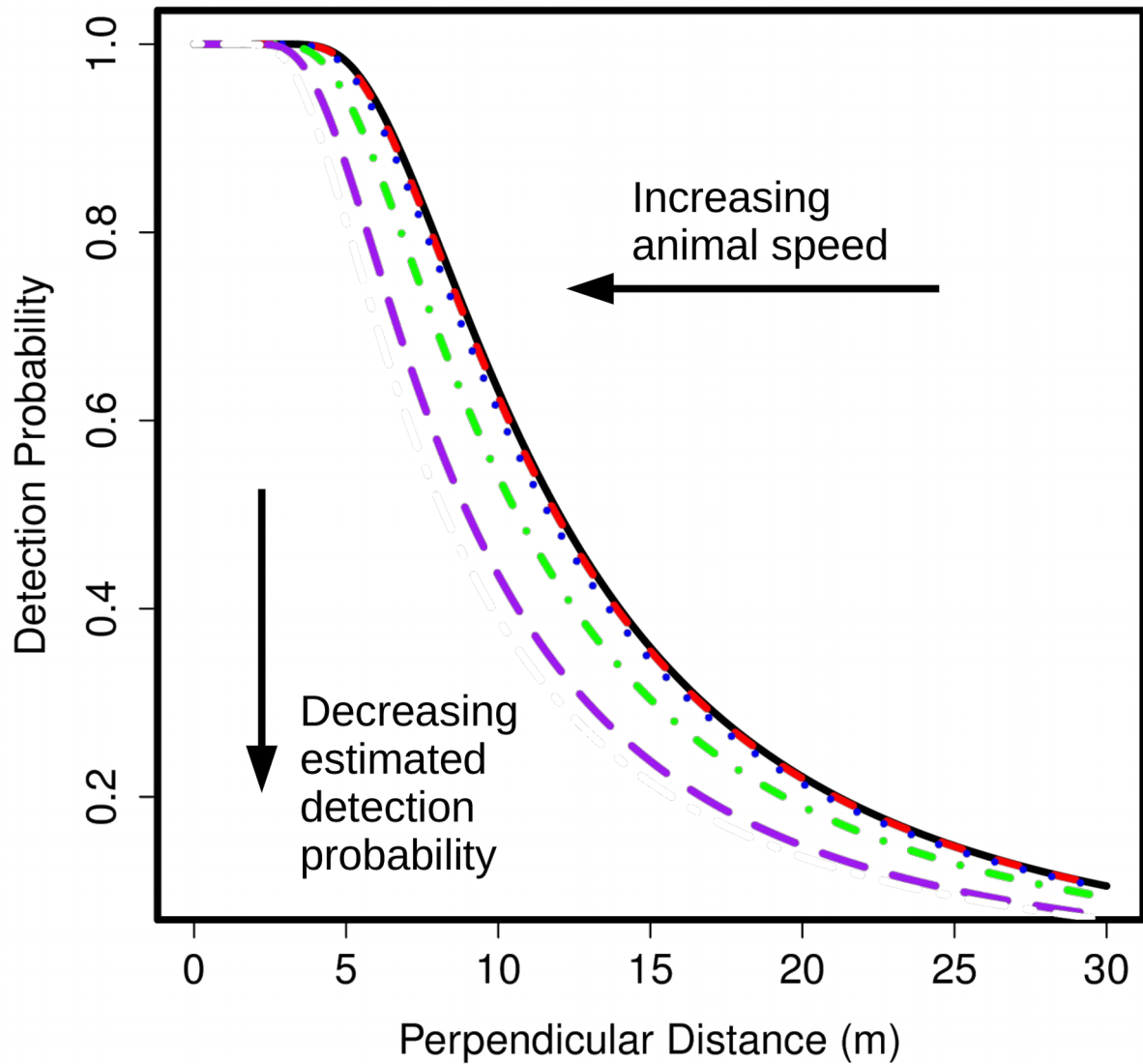
$$\hat{N} = \frac{n}{\hat{p}}$$



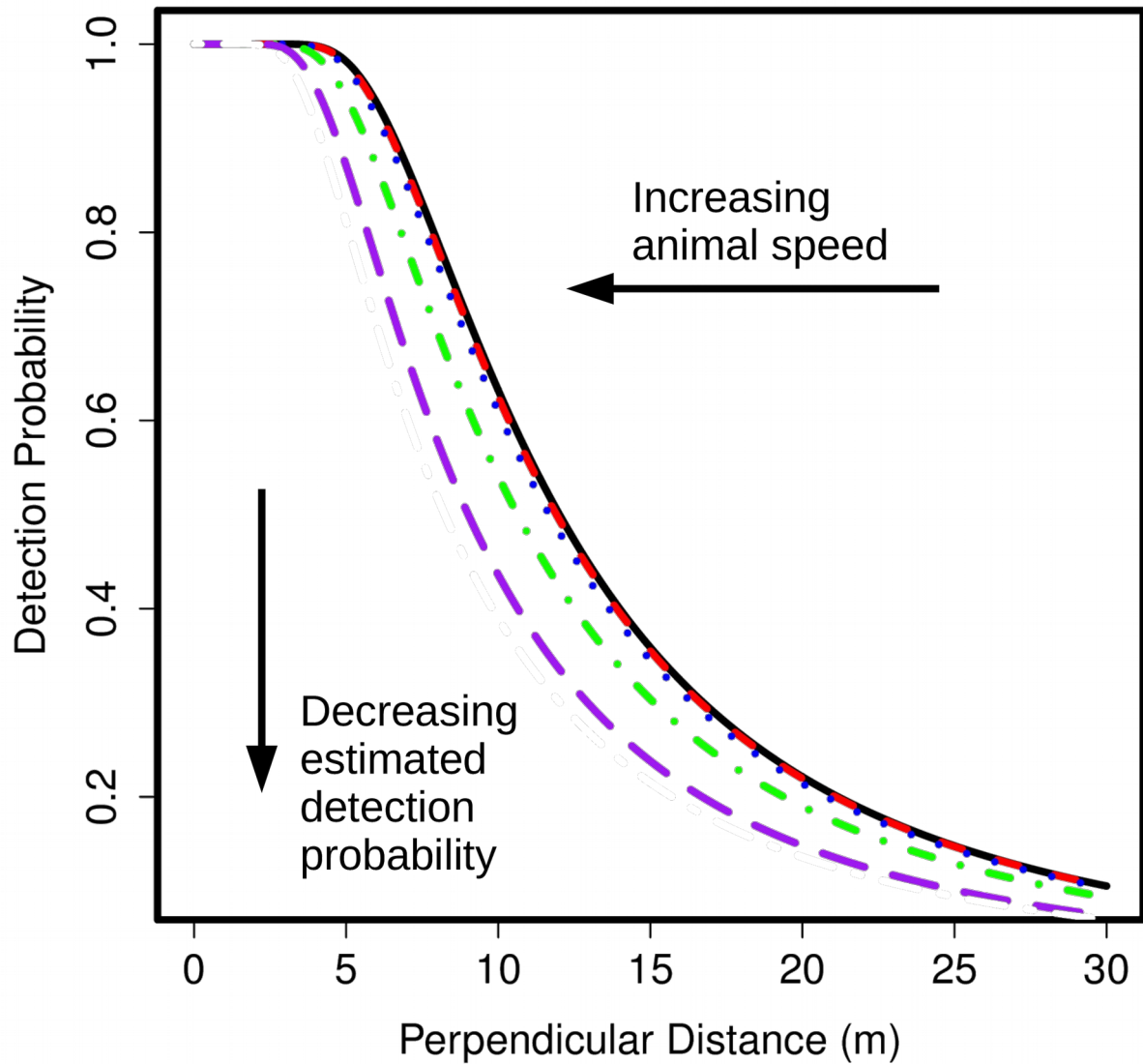
$$\hat{N} = \frac{n}{\hat{p}}$$



$$\hat{N} = \frac{n}{\hat{p}}$$



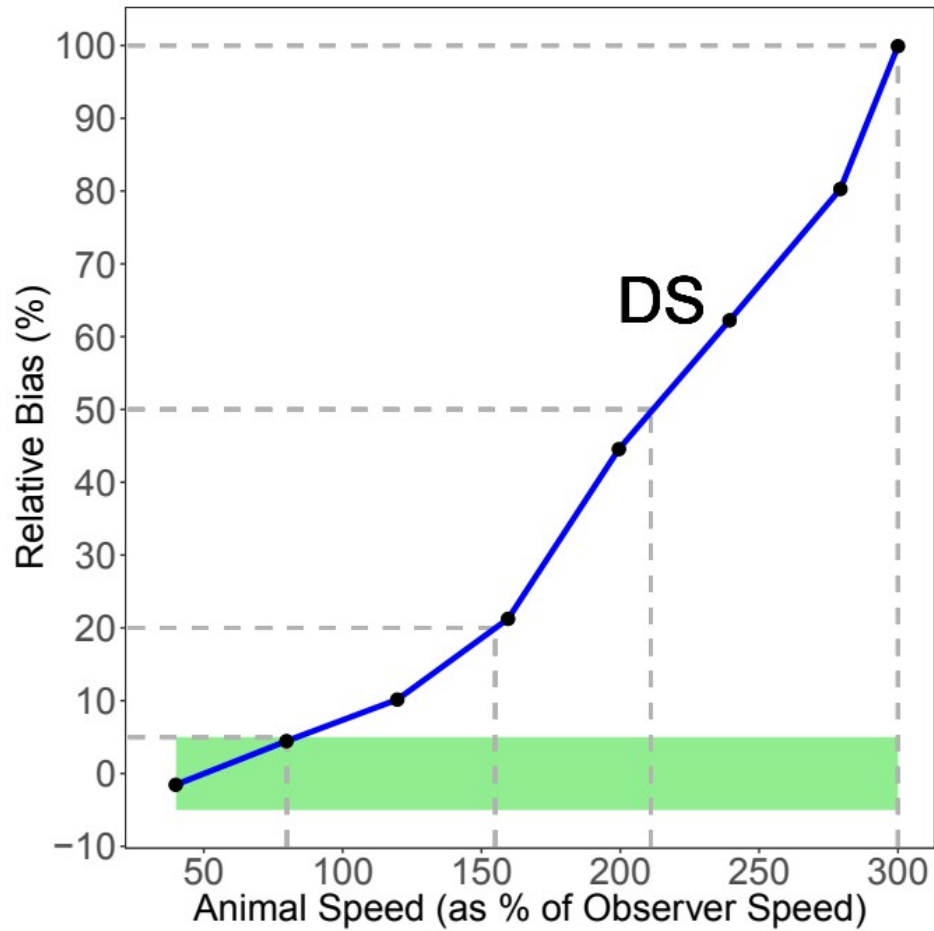
$$\hat{N} = \frac{n}{\hat{p}}$$



$$\begin{array}{c} \uparrow \\ \uparrow \end{array} \hat{N} = \frac{n}{\hat{p}} \begin{array}{c} \uparrow \\ \downarrow \end{array}$$

# SIMULATION

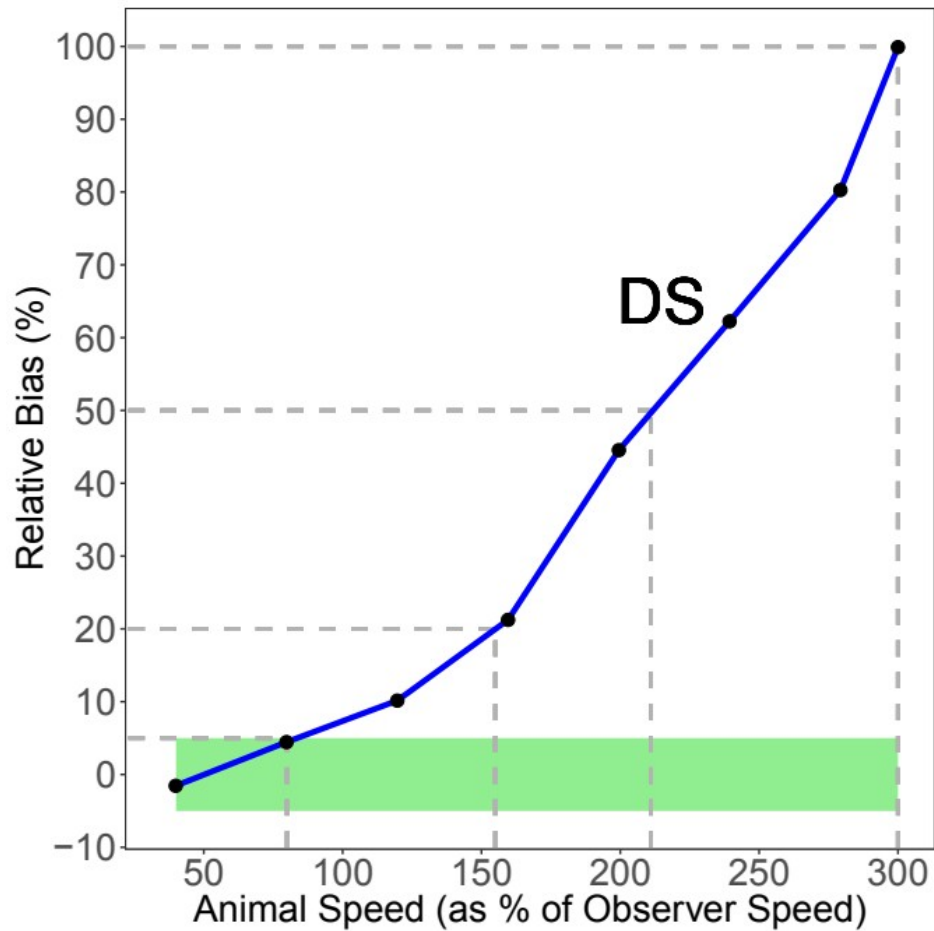
# SIMULATION



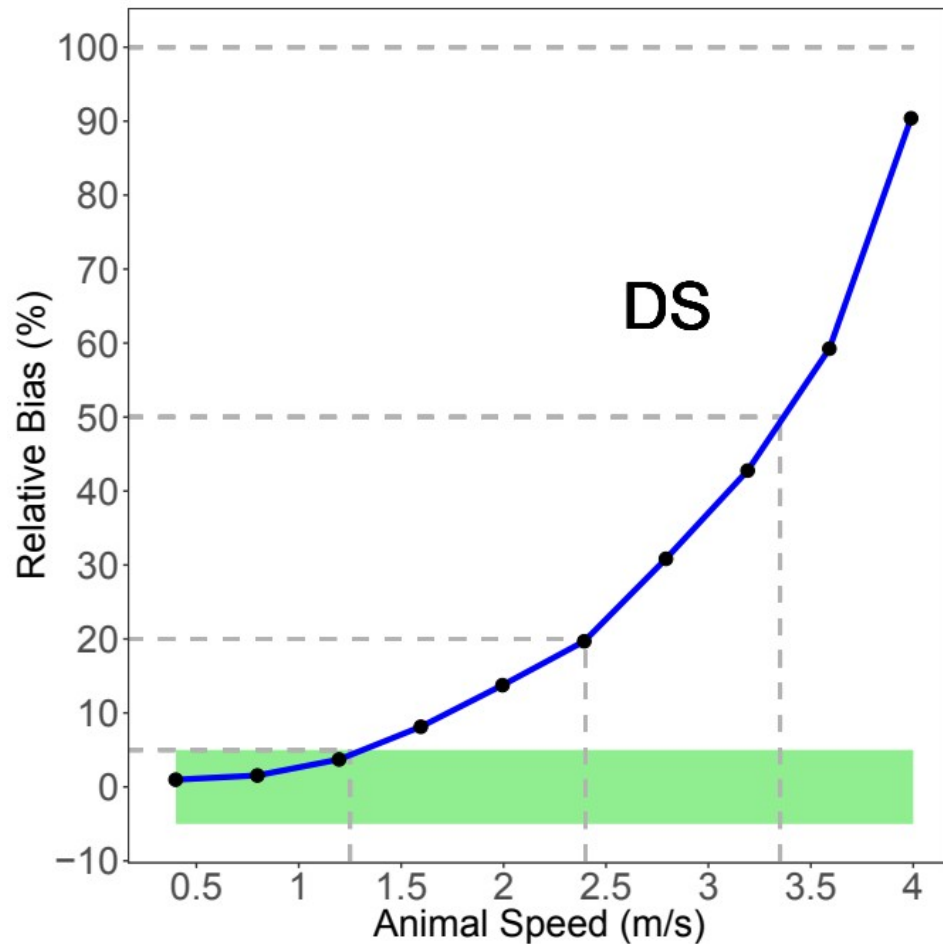
LINE TRANSECTS



# SIMULATION



LINE TRANSECTS



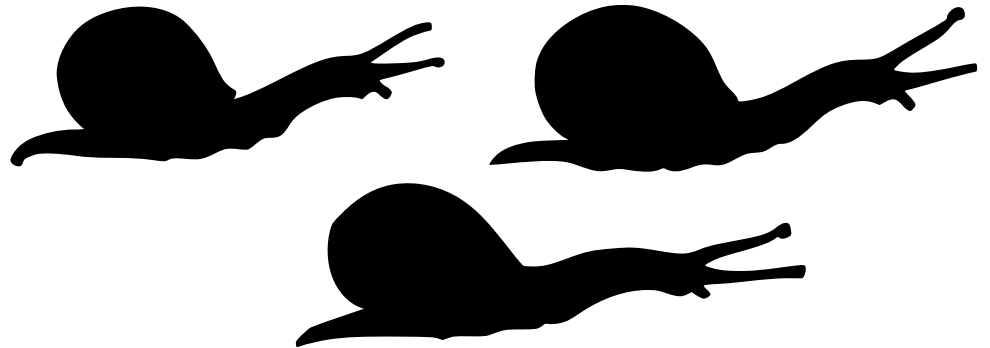
POINT TRANSECTS

**A**ssume: Objects are detected at their *initial* location.

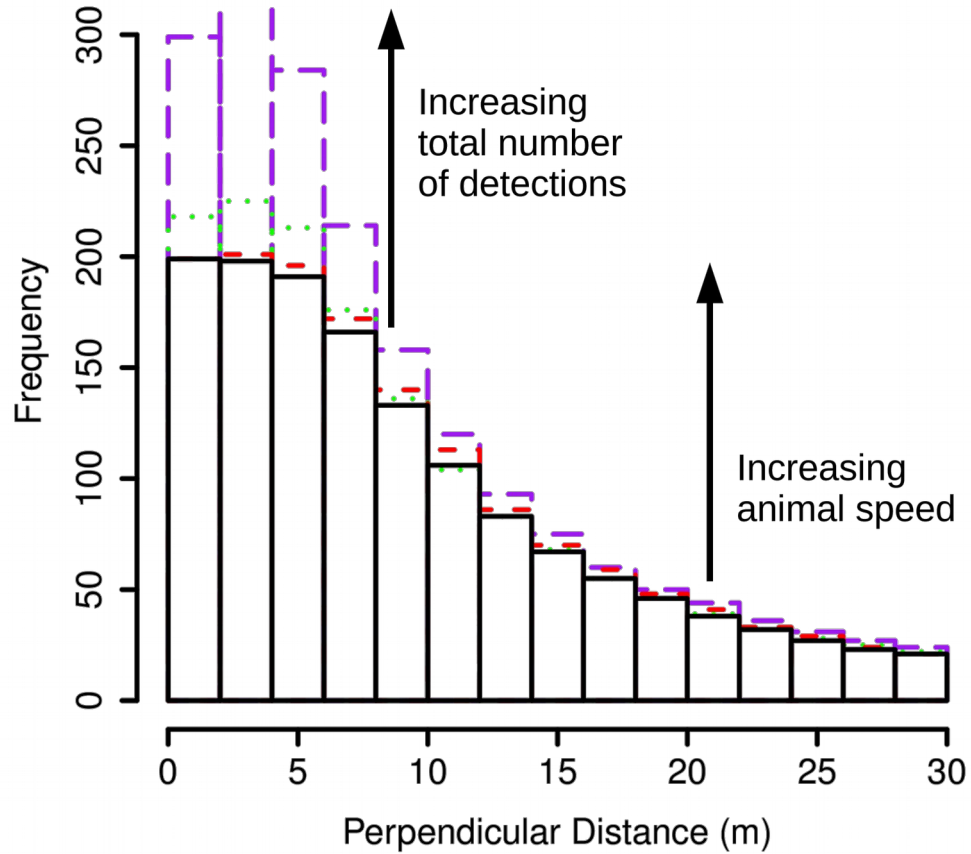
**V**iolate: Move independently of the observer.

**M**itigate:

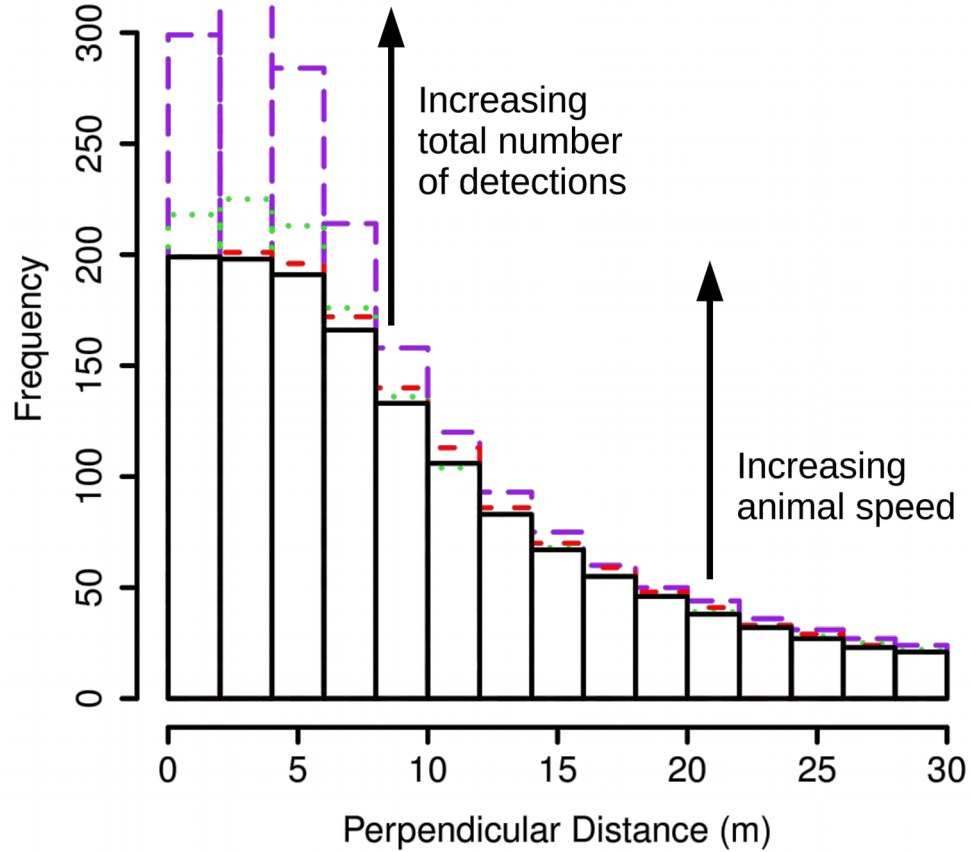
- ✓ Survey Protocol



# SURVEY PROTOCOL



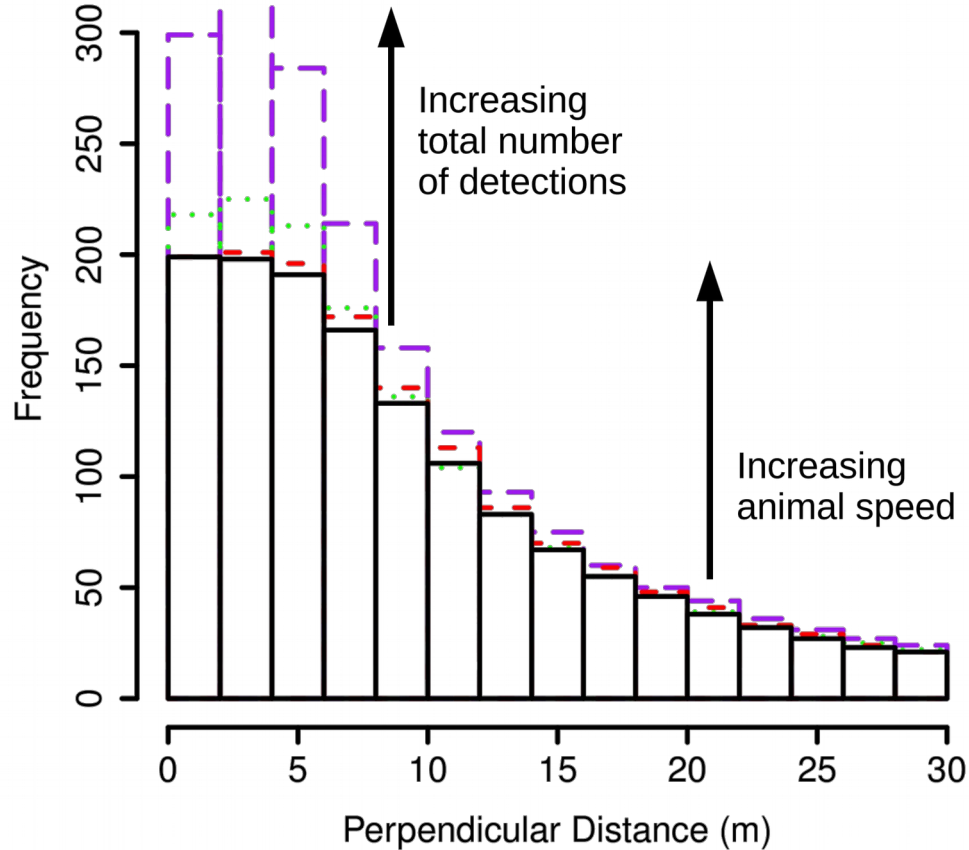
# SURVEY PROTOCOL



1

Search further.

# SURVEY PROTOCOL



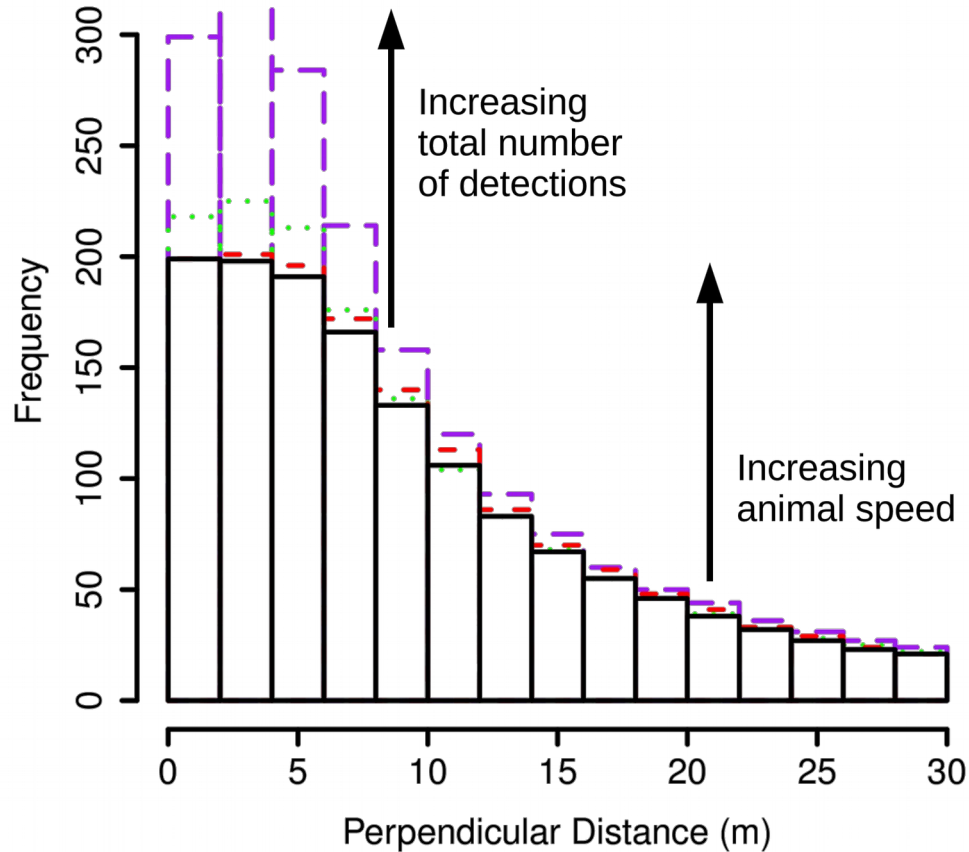
1

Search further.

2

Ignore overtaking animals.

# SURVEY PROTOCOL



1

Search further.

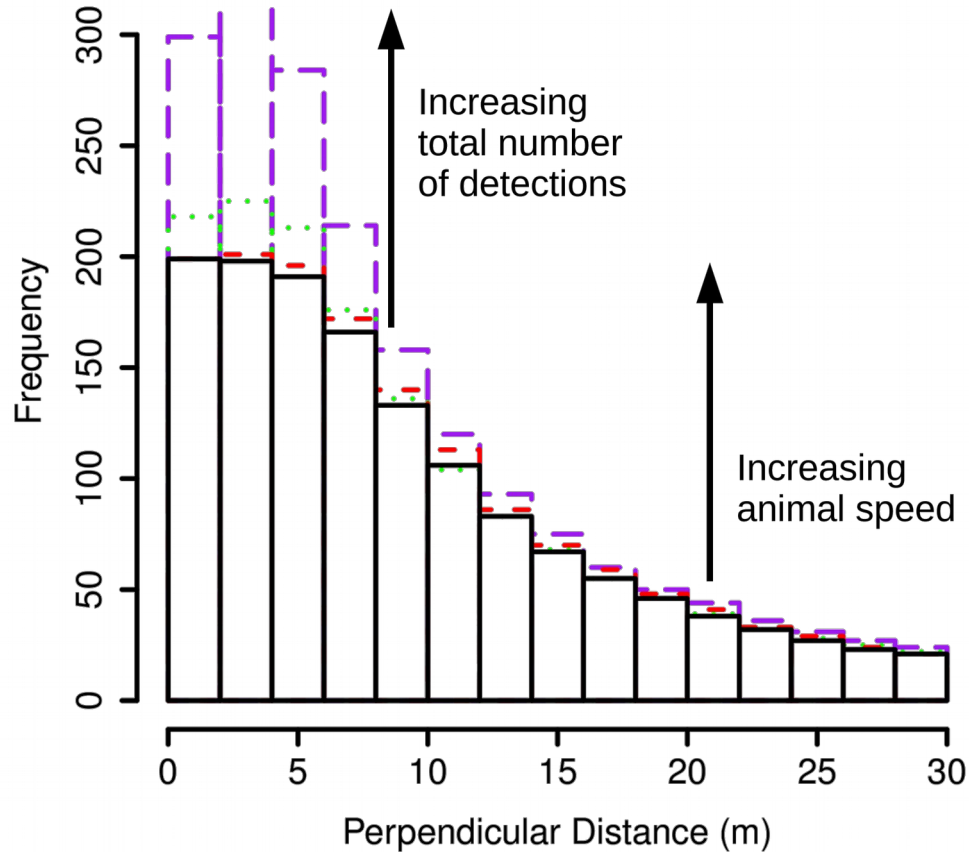
2

Ignore overtaking animals.

3

Take a snapshot.

# SURVEY PROTOCOL



1

Search further.

2

Ignore overtaking animals.

3

Take a snapshot.

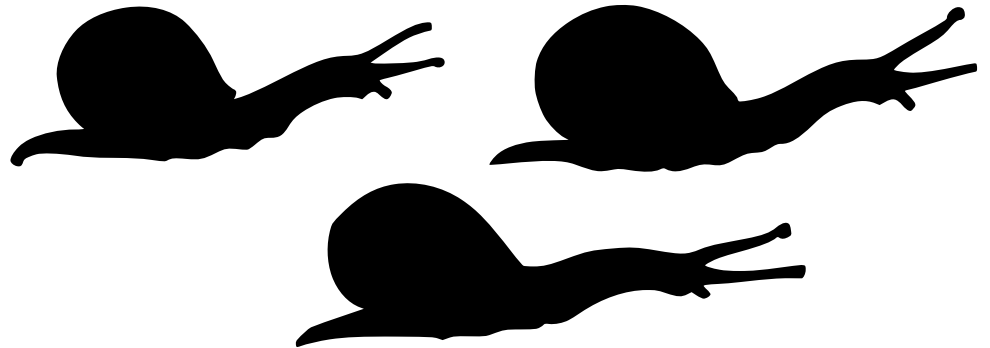
Glennie, R., Buckland, S.T. and Thomas, L., 2015. [The effect of animal movement on line transect estimates of abundance](#). *PloS one*, 10(3), p.e0121333.

**Assume:** Objects are detected at their *initial* location.

**Violate:** Move independently of the observer.

**Mitigate:**

- ✓ Survey Protocol
- ✓ Truncate?





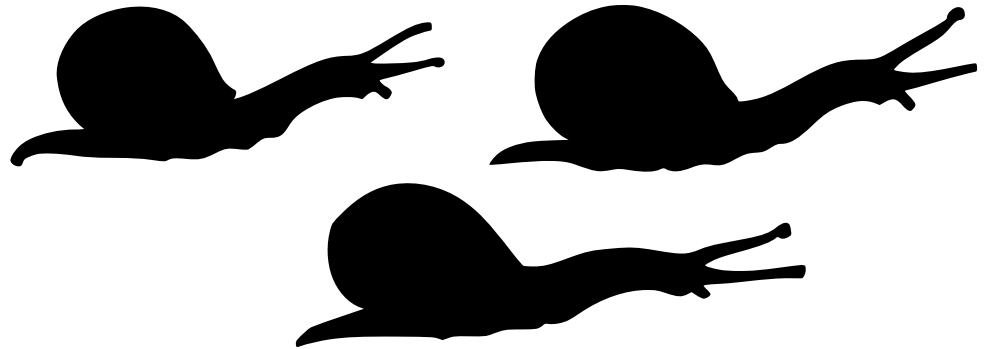
**Assume:** Objects are detected at their *initial* location.

**Violate:** Move independently of the observer.

**Mitigate:**

✓ Survey Protocol

× Truncate?

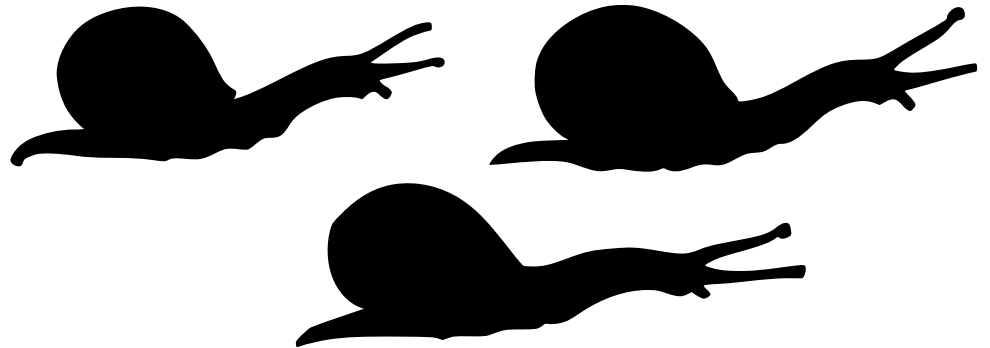


**Assume:** Objects are detected at their *initial* location.

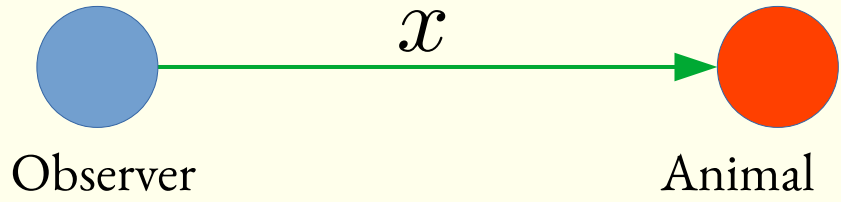
**Violate:** Move independently of the observer.

**Mitigate:**

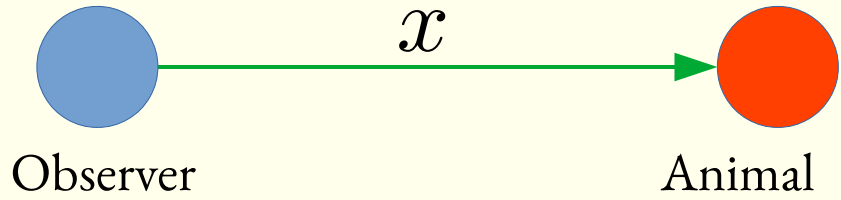
- ✓ Survey Protocol
- ✓ Model?



## DISTANCE SAMPLING

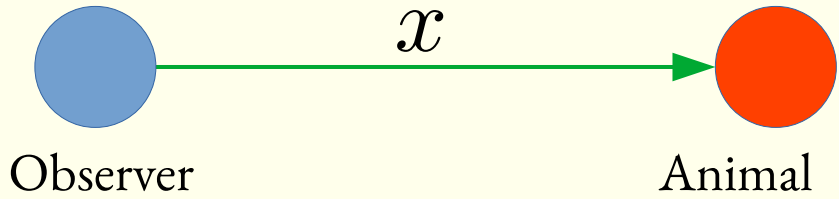


DISTANCE SAMPLING



$$g(x) = \mathbb{P}(\text{detected} \mid \text{located at } x)$$

DISTANCE SAMPLING

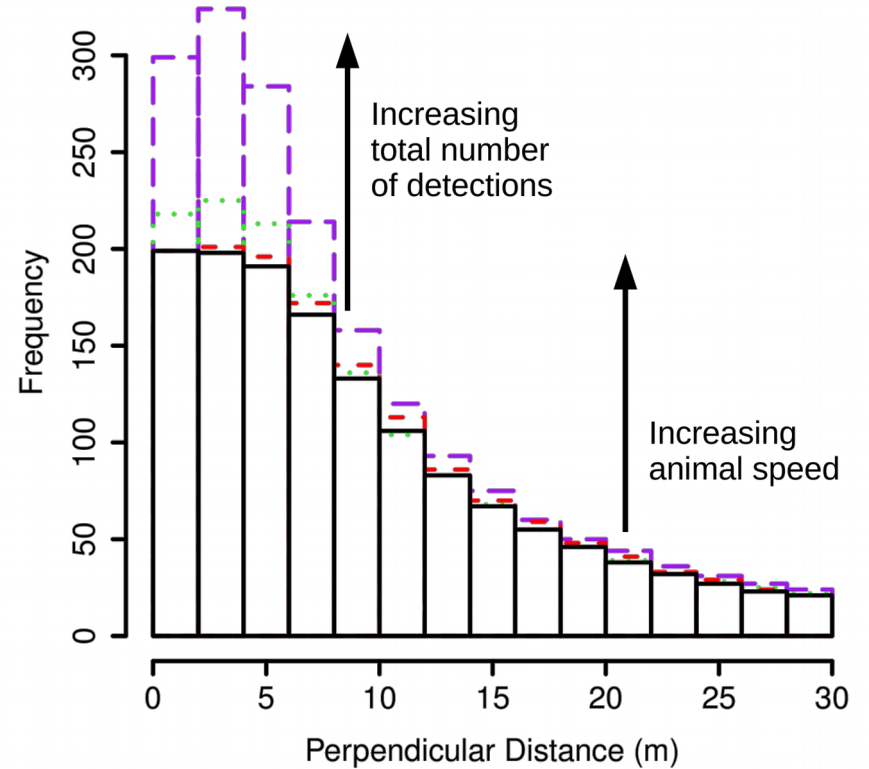


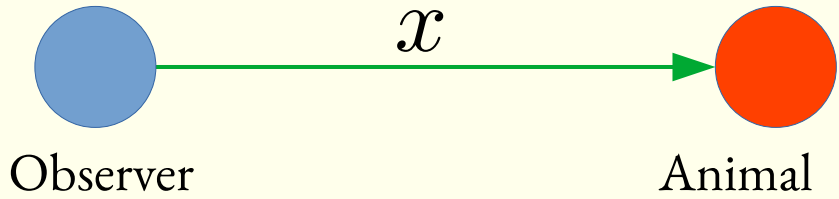
$$g(x) = \mathbb{P}(\text{detected} \mid \text{located at } x)$$

↘

$$f(x) = \frac{g(x)\pi(x)}{\int g(x)\pi(x) dx}$$

## DISTANCE SAMPLING

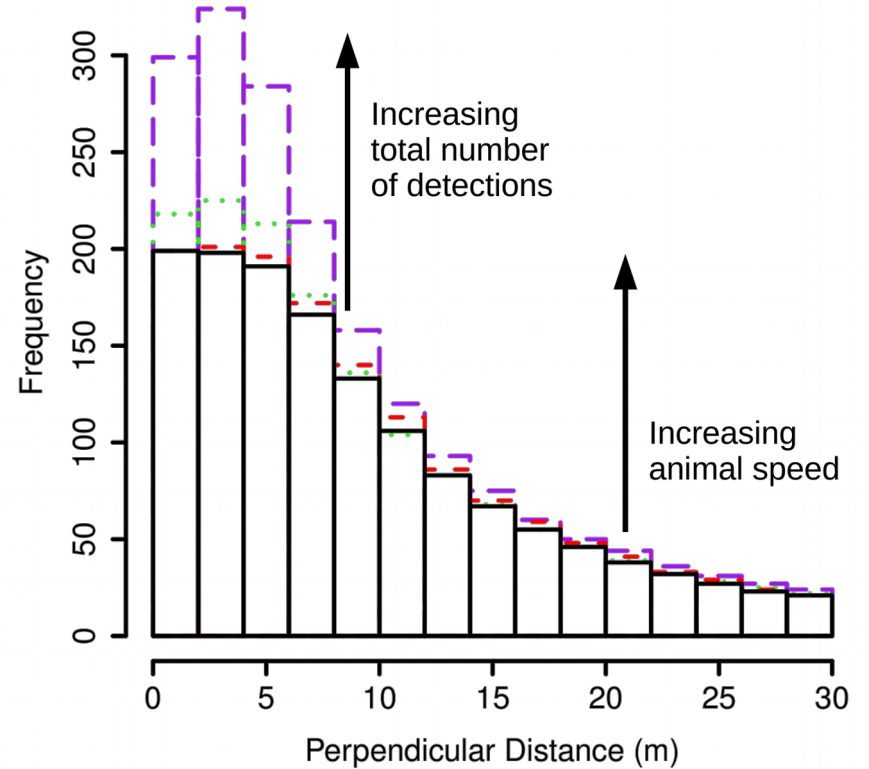




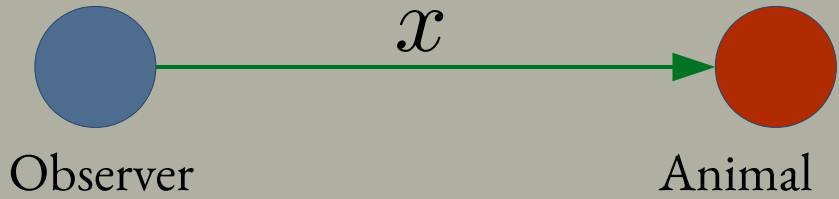
$$g(x) = \mathbb{P}(\text{detected} \mid \text{located at } x)$$

$$f(x) = \frac{g(x)\pi(x)}{\int g(x)\pi(x) dx}$$

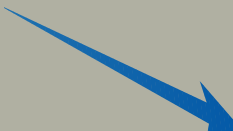
$$\hat{p} = \int \hat{g}(x)\pi(x) dx$$




DISTANCE SAMPLING



$$g(x) = \mathbb{P}(\text{detected} \mid \text{located at } x)$$


$$f(x) = \frac{g(x)\pi(x)}{\int g(x)\pi(x) dx}$$


$$\hat{p} = \int \hat{g}(x)\pi(x) dx$$

DISTANCE SAMPLING



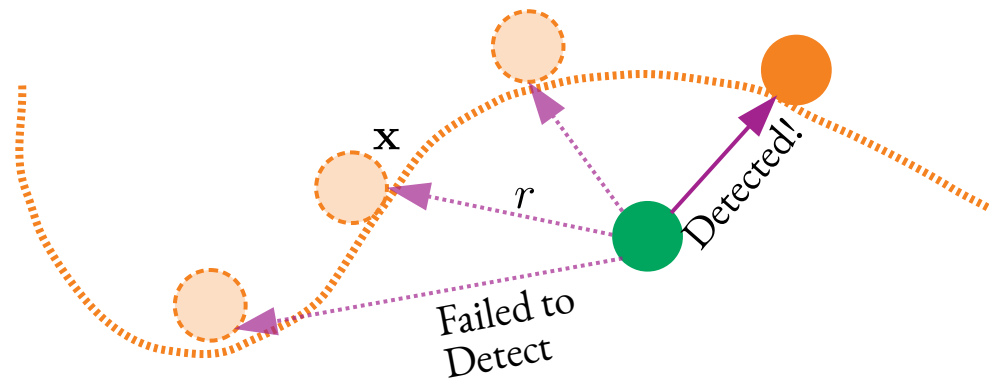


$$g(x) = \mathbb{P}(\text{detected} \mid \text{located at } x)$$

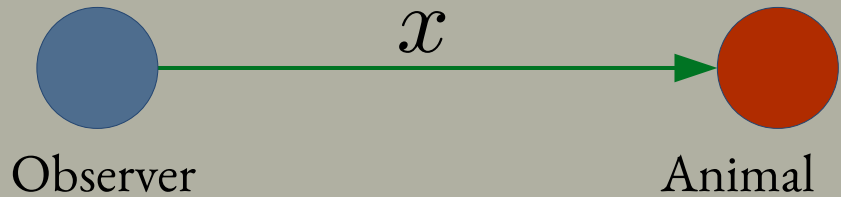
$$f(x) = \frac{g(x)\pi(x)}{\int g(x)\pi(x) dx}$$

$$\hat{p} = \int \hat{g}(x)\pi(x) dx$$

DISTANCE SAMPLING



MDS

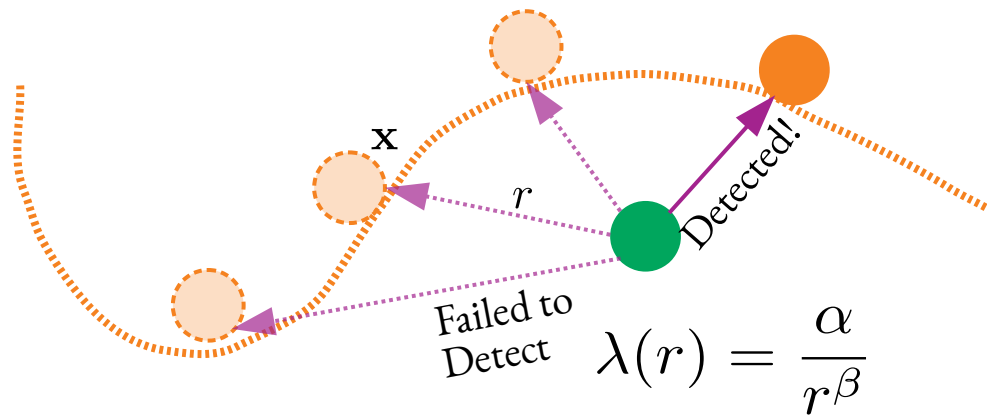


$$g(x) = \mathbb{P}(\text{detected} \mid \text{located at } x)$$

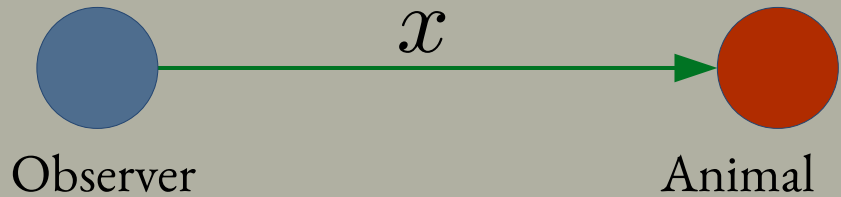
$$f(x) = \frac{g(x)\pi(x)}{\int g(x)\pi(x) dx}$$

$$\hat{p} = \int \hat{g}(x)\pi(x) dx$$

DISTANCE SAMPLING



MDS

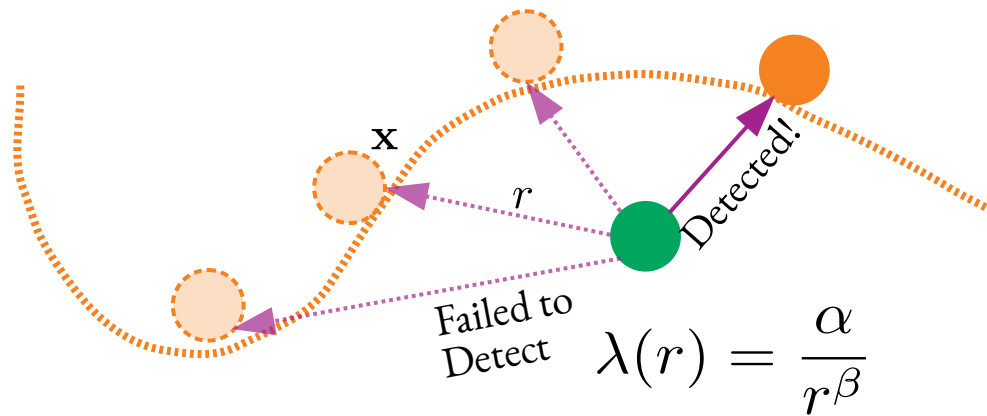


$$g(x) = \mathbb{P}(\text{detected} \mid \text{located at } x)$$

$$f(x) = \frac{g(x)\pi(x)}{\int g(x)\pi(x) dx}$$

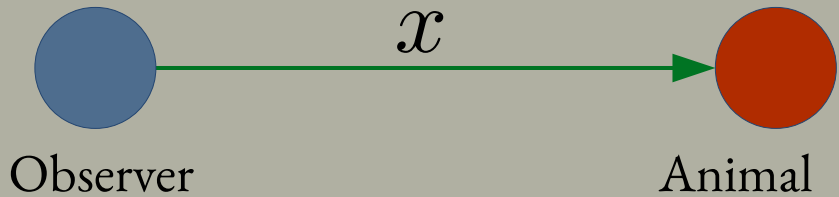
$$\hat{p} = \int \hat{g}(x)\pi(x) dx$$

DISTANCE SAMPLING



$$g(\vec{x}, t) = \lambda(\vec{x}_t) \exp\left(-\int_0^t \lambda(\vec{x}_s) ds\right)$$

MDS

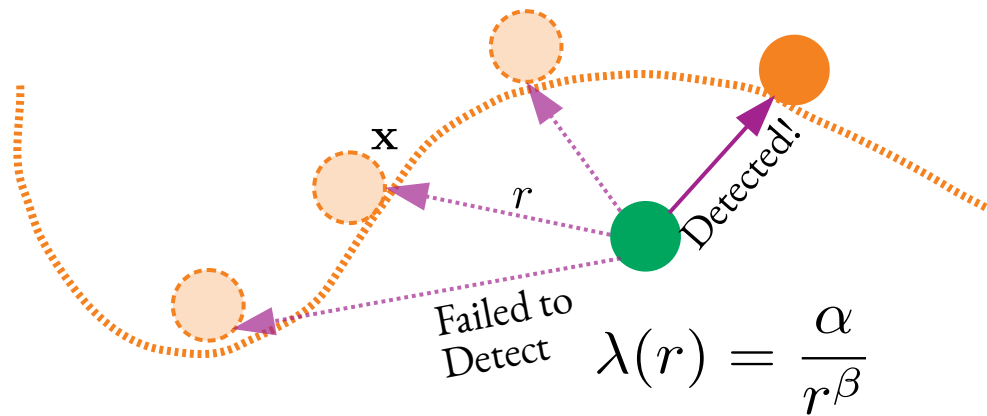


$$g(x) = \mathbb{P}(\text{detected} \mid \text{located at } x)$$

$$f(x) = \frac{g(x)\pi(x)}{\int g(x)\pi(x) dx}$$

$$\hat{p} = \int \hat{g}(x)\pi(x) dx$$

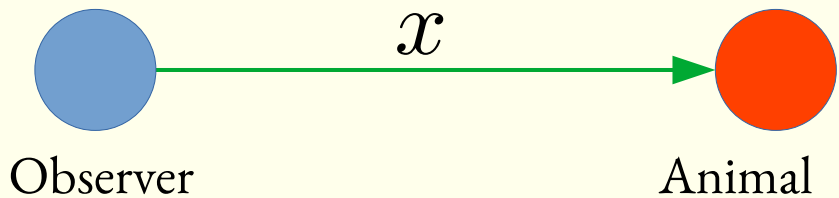
DISTANCE SAMPLING



$$g(\vec{x}, t) = \lambda(\vec{x}_t) \exp\left(-\int_0^t \lambda(\vec{x}_s) ds\right)$$

$$\hat{p} = \int \int \hat{g}(\vec{x}, t)\pi(\vec{x}) dt d\vec{x}$$

MDS

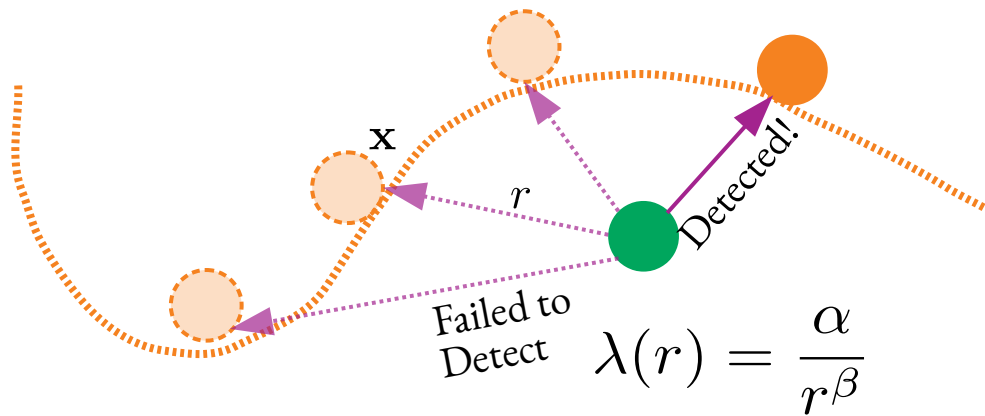


$$g(x) = \mathbb{P}(\text{detected} \mid \text{located at } x)$$

$$f(x) = \frac{g(x)\pi(x)}{\int g(x)\pi(x) dx}$$

$$\hat{p} = \int \hat{g}(x)\pi(x) dx$$

DISTANCE SAMPLING

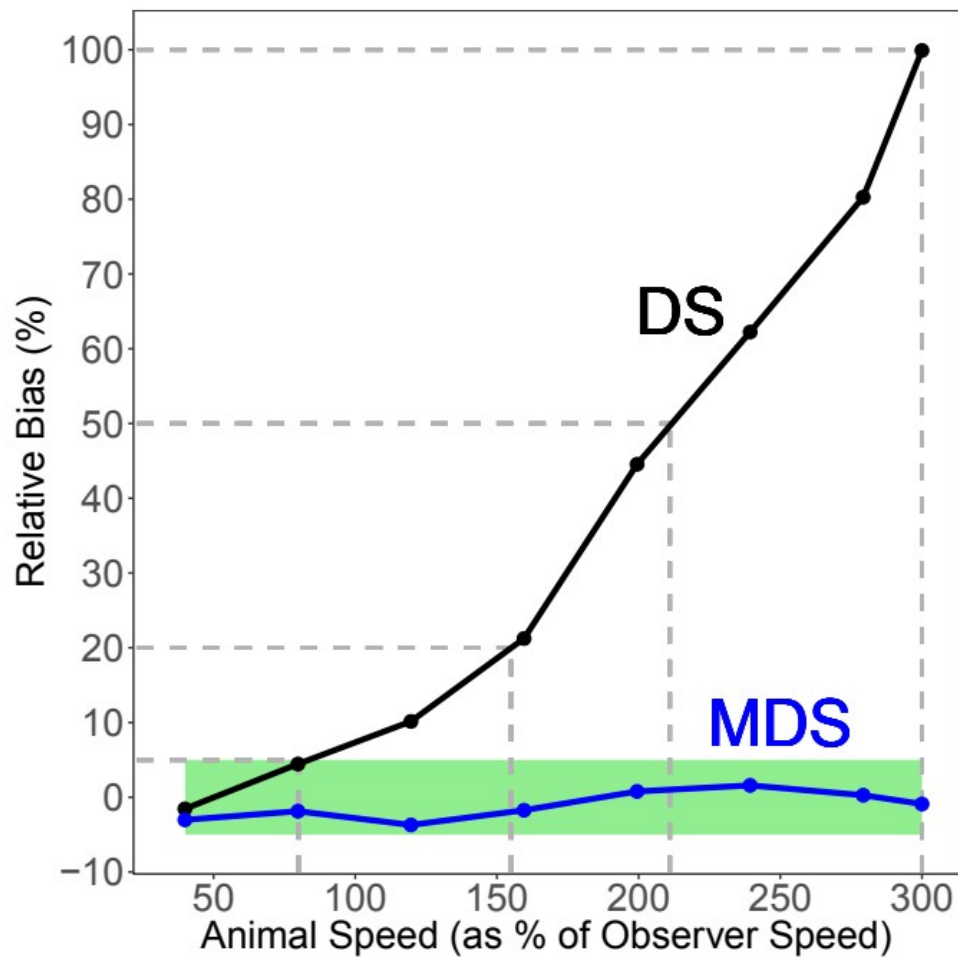


$$g(\vec{x}, t) = \lambda(\vec{x}_t) \exp\left(-\int_0^t \lambda(\vec{x}_s) ds\right)$$

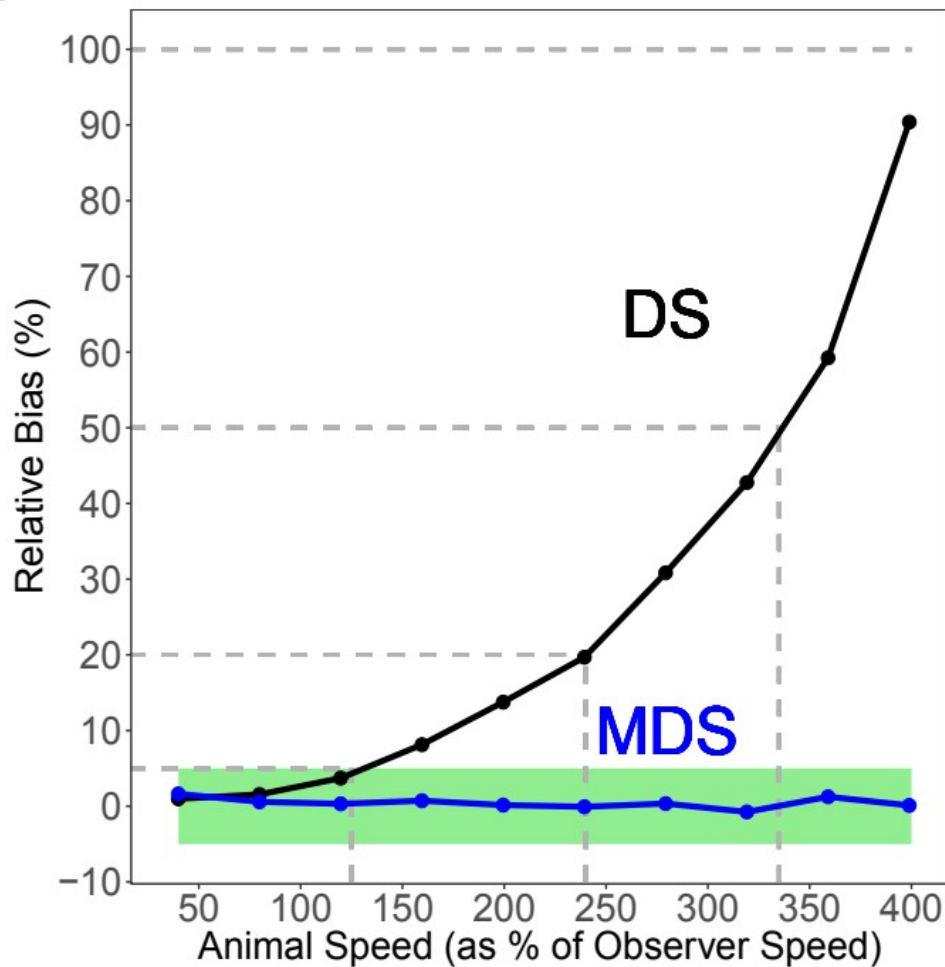
$$\hat{p} = \int \int \hat{g}(\vec{x}, t)\pi(\vec{x}) dt d\vec{x}$$

MDS

# SIMULATION



LINE TRANSECTS



POINT TRANSECTS

# APPLICATION

- Applied to Spotted Dolphins in the Eastern Tropical Pacific.

## APPLICATION



- Applied to Spotted Dolphins in the Eastern Tropical Pacific.
- Use tag data on 19 individuals to estimate movement speed using a Brownian motion movement model.

## APPLICATION

# APPLICATION

- Applied to Spotted Dolphins in the Eastern Tropical Pacific.
- Use tag data on 19 individuals to estimate movement speed using a Brownian motion movement model.
- Animal speed was around 40-50% observer speed.

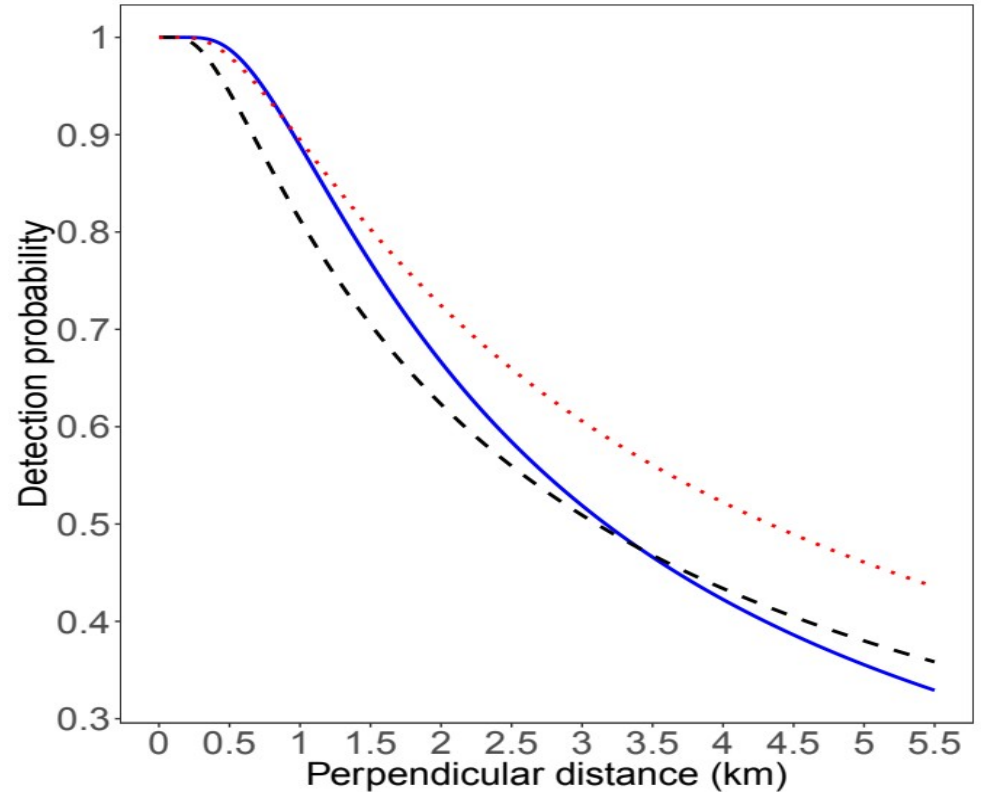
# APPLICATION

- Applied to Spotted Dolphins in the Eastern Tropical Pacific.
- Use tag data on 19 individuals to estimate movement speed using a Brownian motion movement model.
- Animal speed was around 40-50% observer speed.

Year	CDS1D			CDS2D			MDS2D		
	Est.	CV	95% CI	Est.	CV	95% CI	Est.	CV	95% CI
1999	1073	22%	(700, 1644)	1166	18%	(750, 1581)	918	18%	(588, 1248)
2000	947	23%	(601, 1493)	999	19%	(627, 1372)	787	19%	(492, 1082)
2003	1518	19%	(1053, 2189)	1550	15%	(1087, 2013)	1223	15%	(854, 1592)
2006	1213	24%	(755, 1947)	1342	20%	(809, 1874)	1059	20%	(636, 1481)

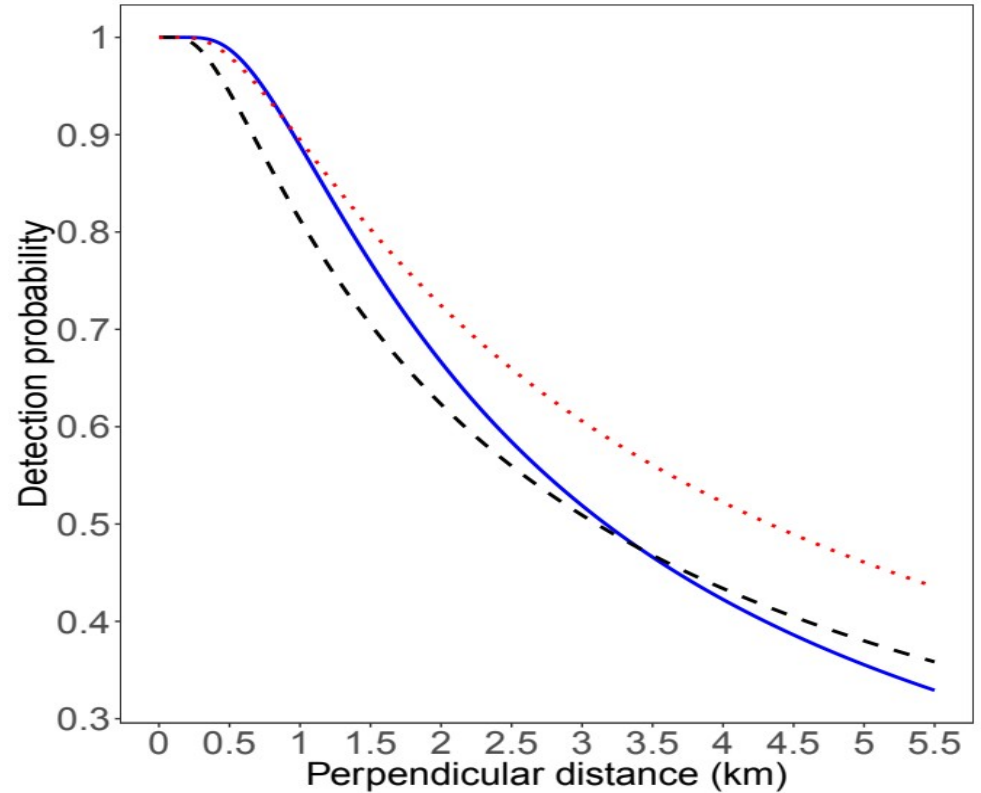
- Applied to Spotted Dolphins in the Eastern Tropical Pacific.
- Use tag data on 19 individuals to estimates movement speed using a Brownian motion movement model.
- Animal speed was around 40-50% observer speed.

## APPLICATION



- Applied to Spotted Dolphins in the Eastern Tropical Pacific.
- Use tag data on 19 individuals to estimates movement speed using a Brownian motion movement model.
- Animal speed was around 40-50% observer speed.

## APPLICATION



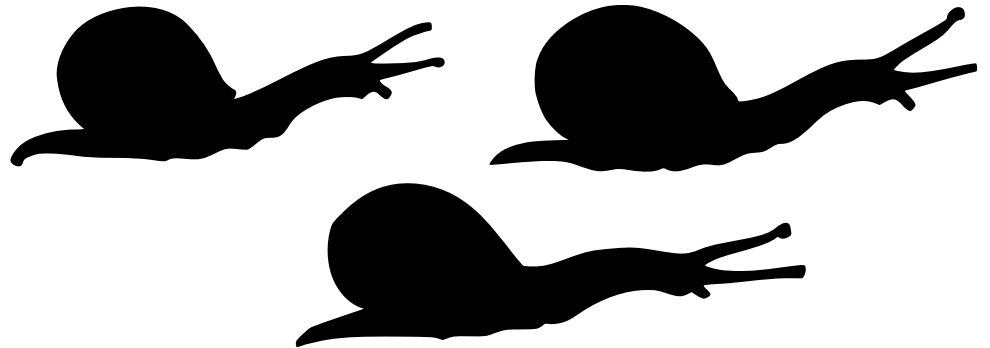
Glennie, R., Buckland, S.T., Langrock, R., Gerrodette, T., Ballance, L., Chivers, S., Scott, M. and Perrin, W., 2019. [Incorporating animal movement into distance sampling](#). *Journal of the American Statistical Association*. *Under Revision*.

**Assume:** Objects are detected at their *initial* location.

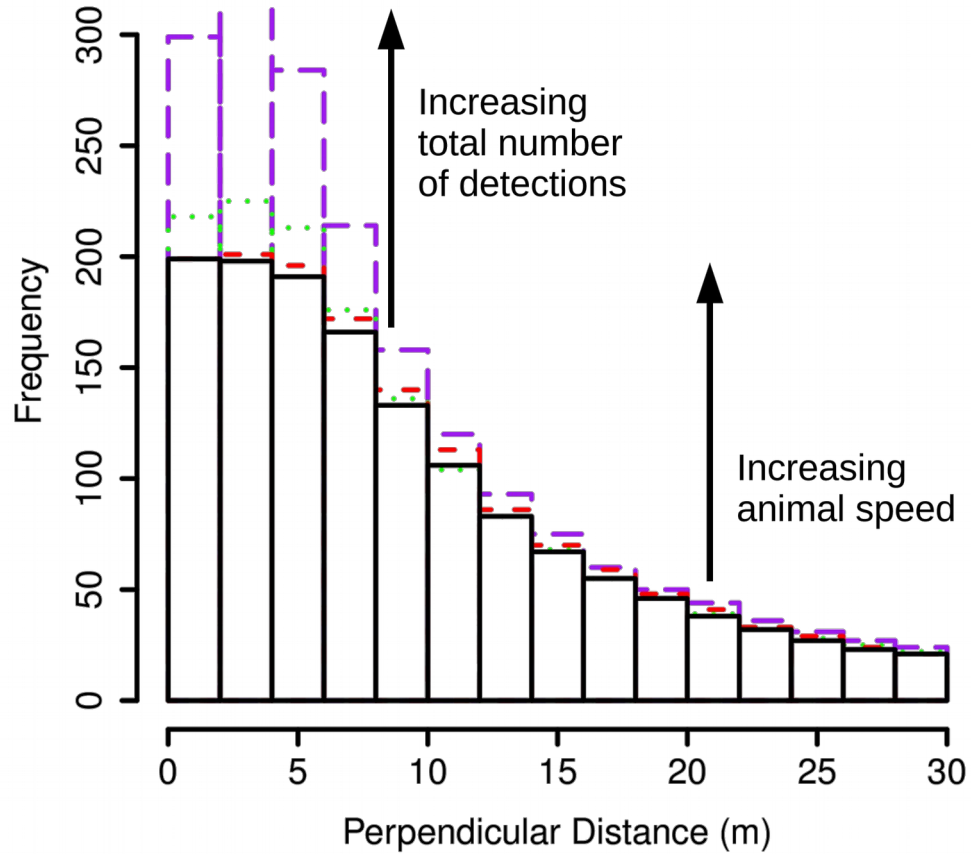
**Violate:** Move independently of the observer.

**Mitigate:**

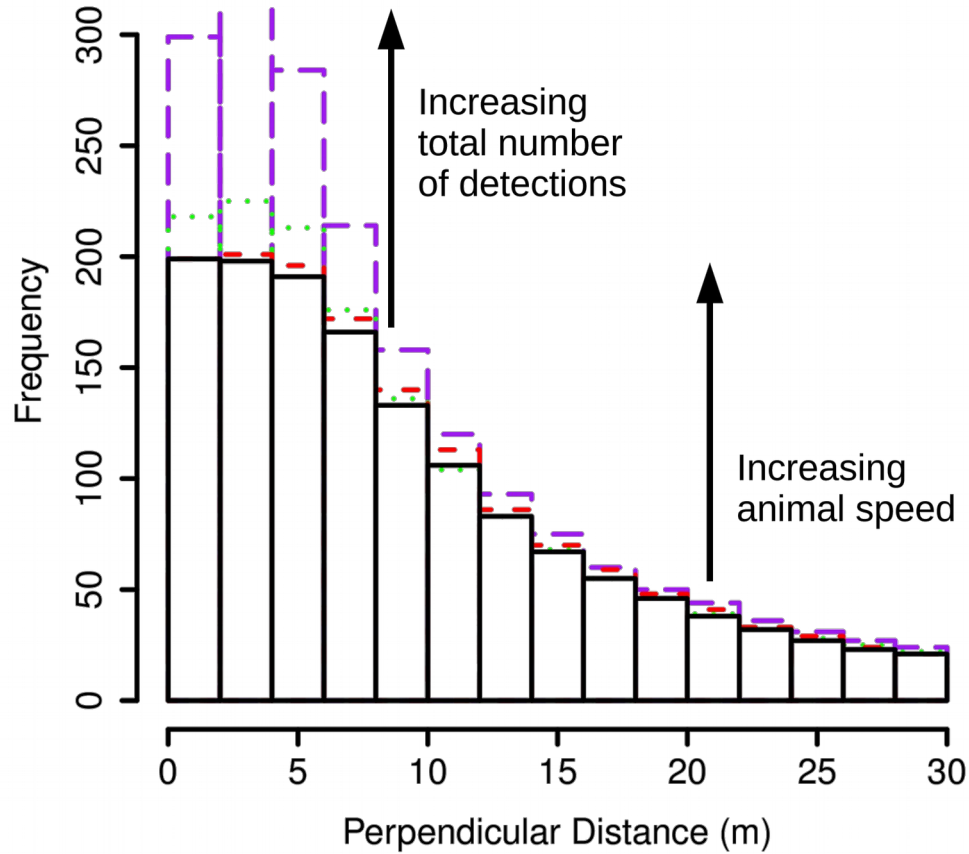
- ✓ Survey Protocol
- ✓ Model



# MODELLING



# MODELLING

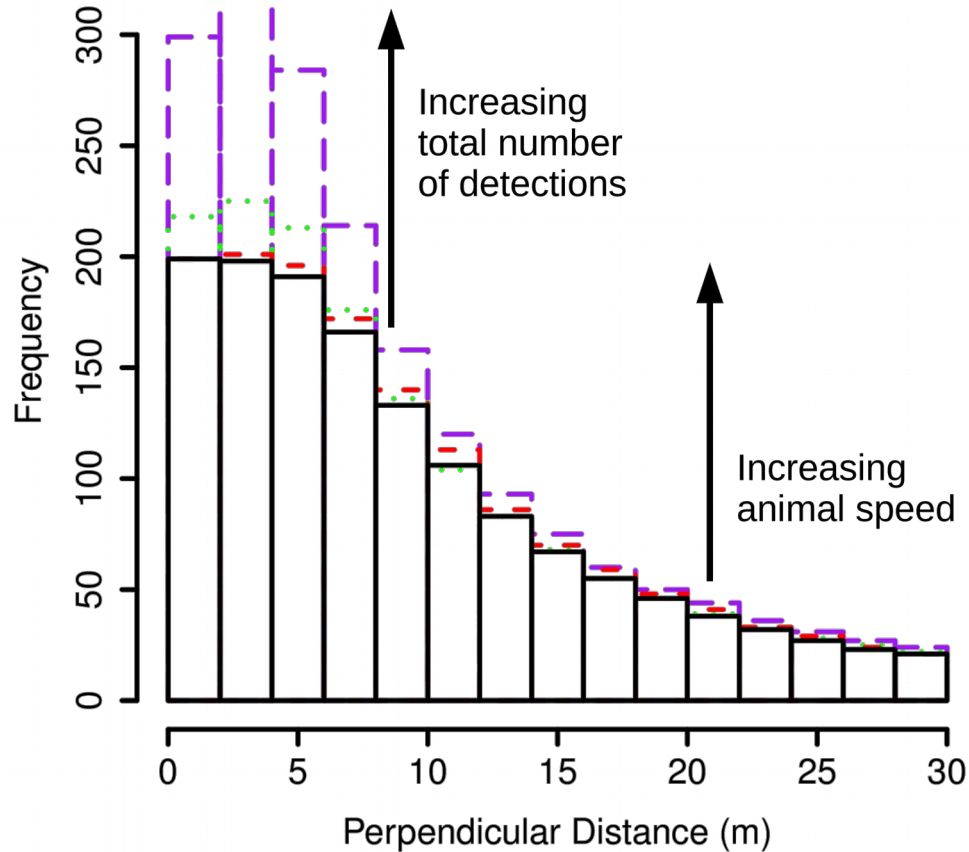


1

Need Detection Times and 2d locations.



# MODELLING



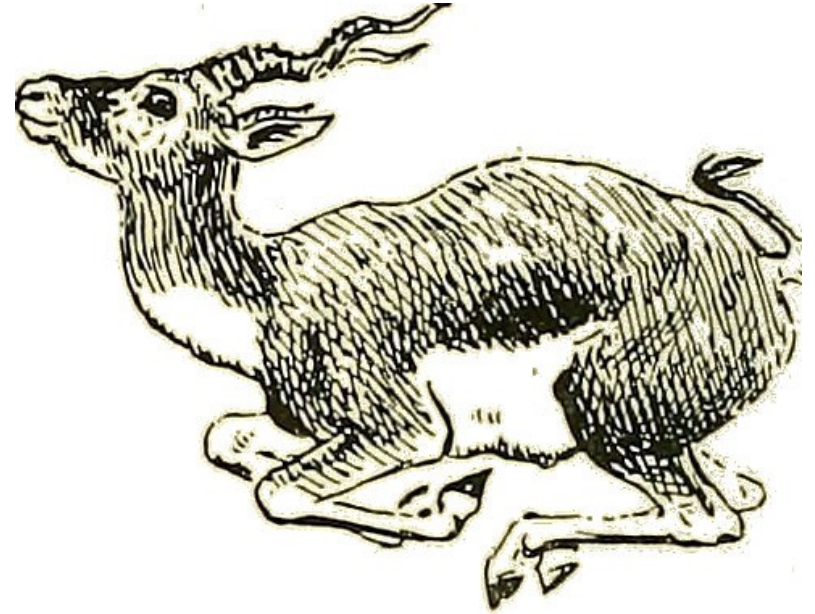
1

Need Detection Times and 2d locations.

2

Need information on movement.

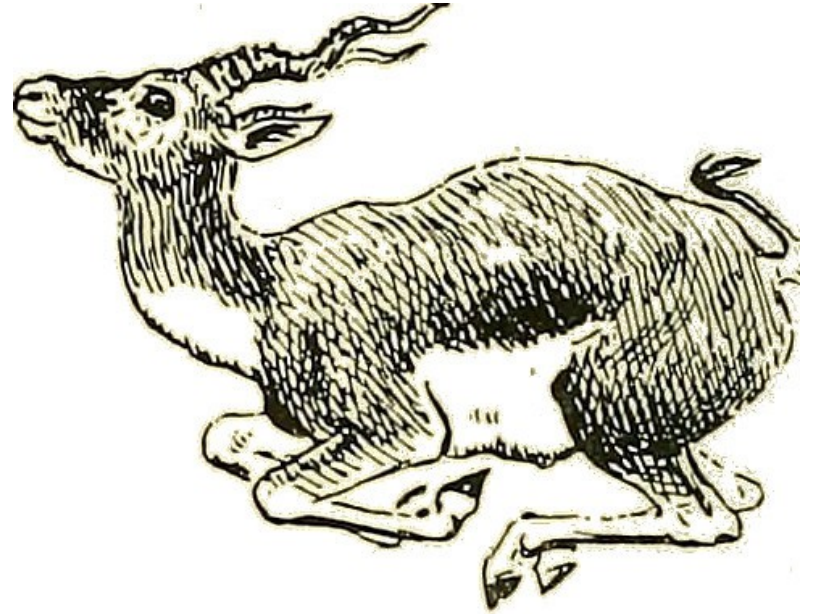
# FURTHER DEVELOPMENTS



# FURTHER DEVELOPMENTS

1

Cameras and Gliders



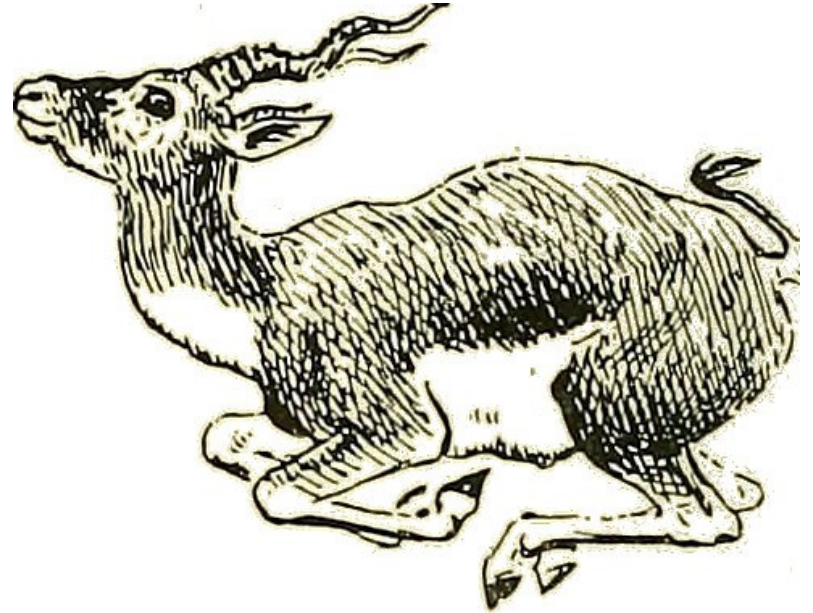
# FURTHER DEVELOPMENTS

1

Cameras and Gliders

2

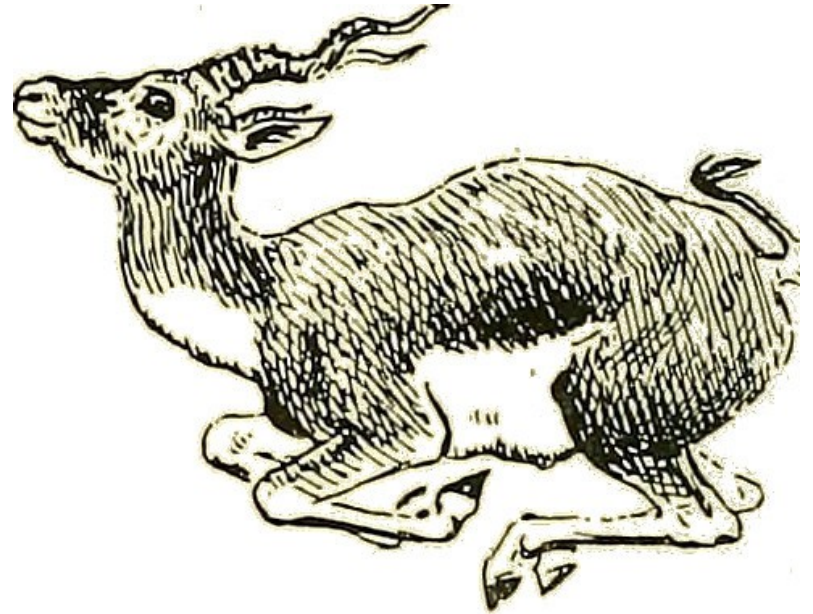
Responsive Movement



Conn, P.B. and Alisauskas, R.T., 2018. Simultaneous modelling of movement, measurement error, and observer dependence in mark-recapture distance sampling: An application to Arctic bird surveys. *The Annals of Applied Statistics*, 12(1), pp.96-122.

# FURTHER DEVELOPMENTS

- 1 Cameras and Gliders
- 2 Responsive Movement
- 3 Behaviour-Switching Movement



Conn, P.B. and Alisauskas, R.T., 2018.  
Simultaneous modelling of movement,  
measurement error, and observer dependence in  
mark-recapture distance sampling: An  
application to Arctic bird surveys. *The Annals of  
Applied Statistics*, 12(1), pp.96-122.

# DISTANCE SAMPLING AND ANIMAL MOVEMENT

README.md

## moveds

Fits models that account for non-responsive, Brownian motion of individuals during distance sampling surveys.

## Install

In R, the latest release can be installed using the `devtools` package with command

```
devtools::install_github("r-glennie/moveds@v0.1.0", build_vignettes = TRUE)
```

The package requires you have a C compiler installed on your system. Windows users may need to install R-tools for this reason. It is assumed Linux and Mac users have a compiler installed.

Richard Glennie  
University of St Andrews  
rg374@st-andrews.ac.uk



University of  
St Andrews



**CREEM**

Centre for Research into Ecological  
and Environmental Modelling