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# Querying and Visualization of Moving Objects Using Constraint Databases

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# Querying and Visualization of Moving Objects Using Constraint Databases

by:

Semere M. Woldemariam

A THESIS

Presented to the Faculty of  
The Graduate College at the University of Nebraska  
In Partial Fulfillment of Requirements  
For the Degree of Master of Science

Major: Computer Science

Under the Supervision of Professor Peter Revesz

Lincoln, Nebraska

July, 2017

# QUERYING AND VISUALIZATION OF MOVING OBJECTS USING CONSTRAINT DATABASES

Semere Woldemariam, M.S.

University of Nebraska, 2017

Advisor: Peter Revesz

Good querying and visualization of moving objects and their trajectories is still an open problem. This thesis investigates three types of moving objects. First, projectiles, whose parabolic motion is difficult to represent. Second, moving objects that slide down a slope. The representation of these objects is challenging because of their accelerating motion. Third, the motion of migrating animals. The motion of migrating animals is challenging because it also involves some spatio-temporal interpolation. The thesis shows a solution to these problems using ideas from physics and an implementation in the MLPQ constraint databases system. The MLPQ implementation enables several complex spatio-temporal queries that are difficult or impossible to implement in other database and GIS systems. The implementation for animal migration uses real migratory sea turtle data obtained from Dr. Lohmann from the University of North Carolina at Chapel Hill. . .

## *Acknowledgements*

First, I would like to acknowledge my advisor Dr Peter Revesz for his patient guidance. Second, thanks to my thesis committee members Dr Lisong Xu and Dr Ashok Samal for reviewing my work for its betterment . . .

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*Dedicated to my late father Mihreteab Woldemariam and my  
mother Tiblets Fitawu...*

## Chapter 1

# Introduction

### 1.1 Background

It may be fair to say, moving object constraint database is not a new concept now. However, the representation of accelerating objects in a constraint database, so that to be able to query them and be able to visualize them, still has its challenges. For example, arcGIS and Oracle Spatial either don't represent the motion of all continuous rigid motions of objects or don't represent accelerating objects. This thesis presents the representation of some accelerating objects, based on physics concepts, and hence be able to query and visualize them using MLPQ system.

MLPQ (Management of Linear Programming Queries) is a constraint -relational database system that is continuously built and upgraded at the University of Nebraska - Lincoln, since 1995 [3][4][5]. It extends the relational database by incorporating data represented by a linear function over  $k$  attribute variables. The linear function serves as a bound for the data by the linear inequality relation of the attributes, hence it is a constraint database. Several query operations can be performed on the data, same way as in relational database, but enhanced as it is not limited to a finite data. Such data constrained by the linear function constitutes a *constraint database*.

Constraint database may represent different kinds of data. For example, *geographic*

*constraint database* is concerned with the representation of objects and phenomena occurring on the surface of the earth [3][4][5]. It may be considered as a database used to represent a region, such as, countries, cities, roads, rivers, mountains, train and telephone line networks, weather patterns, etc [3][4][5].

Constraint database can also represent the data for a moving object. Such database is called a *moving objects constraint database* [3][4][5]. Basically, a moving object database can be assumed as the temporal history of a geographic constraint database. Geographic constraint database and moving object constraint database inspired this thesis to revisit old physics problems, that involve acceleration, and to have look at an actual animal migration research from a constraint database perspective.

## 1.2 Thesis Outline

The physics problems revisited are the *projectile motion* and *inclined plane* problems. In Chapter 2 the representation of the projectile motion in constraint database along with its querying and visualization is presented. Projectile motion problem involves understanding the trajectory of an object under a sole influence of gravitational force, after acquiring a certain magnitude initial velocity [2].

In Chapter 3, the thesis focuses on an inclined plane. Inclined plane problem involves additional forces other than gravitational force. It studies the motion of an object on an inclined plane, which is a tilted surface up on which another object can move ( or simply sit, for that matter). Here, it is investigated if constraint database would be able to represent the trajectory of a projectile and the motion of an object on an inclined plane; thereby to be able to query the database for information, and also visualize it.

In Chapter 4, constraint database representation of migrating sea turtles is presented. Dr Lohmann ( University of North Carolina - Chapel Hill), et al, [7], are studying the migration of sea turtles in the Atlantic ocean and their homing behavior. Some of their data, courtesy of Dr. Lohmann, is used to try to visualize the migration of the sea turtles using constraint database in MLPQ system. That helps convert a finite data to a constraint database, representing infinite data, hence to be able to have a continuous visualization of the migration of the sea turtles, instead of dotted data.

### 1.3 Major Thesis Contribution

The representation of accelerating objects in a constraint database has its challenges. By showing the representation of accelerating objects, whose motion is well defined by physics theory, using linear piecewise approximation, may give an insight for a future more generic approach to the problem.

Matlab can visualize equations. However, it cannot query a set of constraint objects in any easy way. For example the question, from section 4.5, "*Find the Easternmost at time 250 hours.*" is not doable in any easy way. However as we showed in section 4.5, that query can be implemented in the MLPQ constraint database system by two simple extended SQL queries. Hence a contribution of this thesis is showing a simple database approach to querying scientific moving objects data.

## Chapter 2

# Constraint Database Representation of a Projectile Motion In MLPQ System

Projectile motion is one of the classical physics problems. The projectile motion of an object is well defined given certain initial parameters. These parameters are related to each other mathematically via some physics laws. Such relationship between the parameters is the basis for generating several different exercise questions and problems in physics textbooks. Here, the thesis looks at this physical problem, from a database perspective, to explore if it is possible to represent the projectile with a constraint database, thereby be able to do database query to find information about the projectile, and also to be able to visualize it. Hence, the objective of this chapter is to try to represent a projectile motion using constraint database in MLPQ system, and to try to be able to query the constraint database and visualize it.

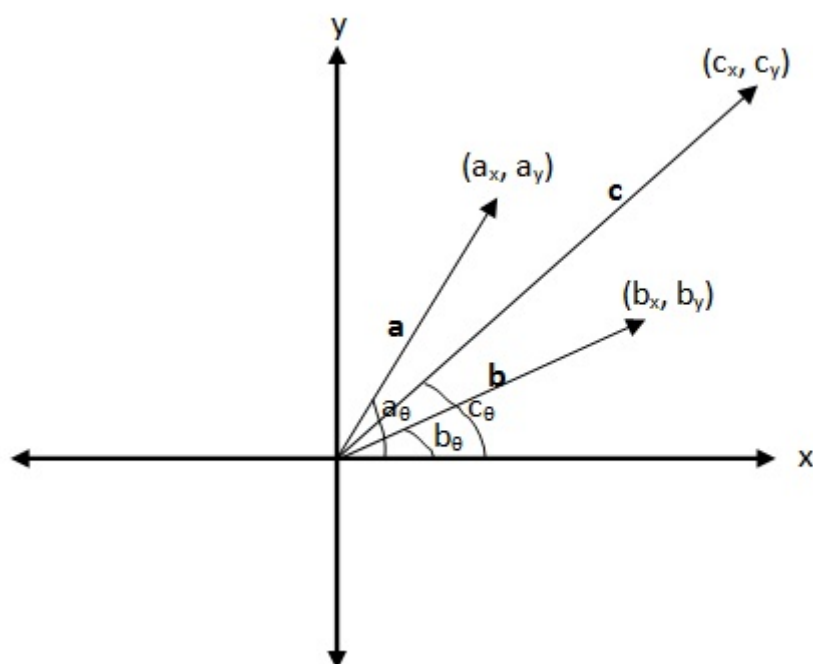
### 2.1 Background – Projectile Motion Problem

A *projectile* is anything that is given an initial velocity and then follows a path determined entirely by the effects of gravitational acceleration (and air resistance) [1]. A batted baseball, thrown football, a package dropped from an air plane, and a bullet shot from a rifle are all examples of projectiles. The path followed by a projectile is

called its *trajectory*[1]. The concepts of *vector* and *one-dimensional motion*, with constant and accelerated velocities, are important background concepts for projectile motion.

### 2.1.1 Vectors

Physical quantities are categorized as scalar and vector quantities. Physical quantities that have both numerical (with unit) and directional properties are vector quantities[2]. The quantities that can be described only by a numerical value (with unit) are called scalar quantities. The sum of scalar quantities is simply the arithmetic sum of the numerical values of the individual scalar quantities. However, adding vector quantities is more complicated. As an example, consider two vector quantities **a** (vectors are denoted by bold faced letters) and **b** as shown in Figure 2.1. If **c** is assumed to be the



---

FIGURE 2.1: The addition of vector quantities. **c** is the vector sum of vectors **a** and **b**.  $a_x$  and  $a_y$  are the  $x$  and  $y$  components of vector **a**, respectively. Similarly,  $b_x$  and  $b_y$  are the  $x$  and  $y$  components of vector **b**, respectively.

vector sum of vectors **a** and **b**, then the magnitude of vector **c** is given by,

$$c_x = a_x + b_x \quad (2.1a)$$

$$c_y = a_y + b_y \quad (2.1b)$$

$$c = \sqrt{c_x^2 + c_y^2} \quad (2.1c)$$

The direction of the vectors **a**, **b**, and **c** is given in terms of the angles that the vectors make with respect to the positive x-axis. That is,

$$a_\theta = \arctan\left(\frac{a_y}{a_x}\right) \quad (2.2a)$$

$$b_\theta = \arctan\left(\frac{b_y}{b_x}\right) \quad (2.2b)$$

$$c_\theta = \arctan\left(\frac{c_y}{c_x}\right) \quad (2.2c)$$

### 2.1.2 One Dimensional Motion

One dimensional motion is a motion along a straight line [2]. One dimensional motion may have a constant velocity, or it may be accelerating. If we assume the direction of motion of an object is along the positive x-axis starting from the origin, then for a constant velocity **v** motion, the position **x** at a time *t* is given by:

$$\mathbf{x} = \mathbf{v}t \quad (2.3)$$

If the motion is an accelerating motion, then the position of the object is given by,

$$\mathbf{x} = \mathbf{v}_o t + \frac{1}{2} \mathbf{a} t^2 \quad (2.4)$$

where **a** is the acceleration of the object.

Projectile motion is the vector sum of a constant velocity horizontal motion and an accelerated vertical motion. The horizontal motion has a velocity equal to the horizontal component of the initial velocity throughout the trajectory. The vertical component of the projectile motion is an accelerating motion. The acceleration is due to gravity, which is approximately  $\mathbf{g} = 9.8m/s^2$ .

## 2.2 Implementation of Constraint Database - Projectile Motion

Consider the projectile trajectory in Figure 2.2

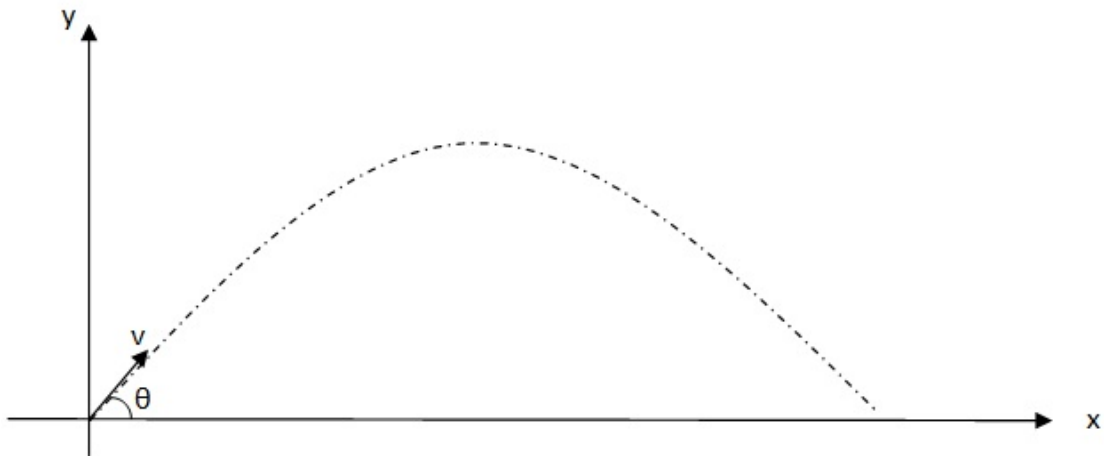


FIGURE 2.2: The trajectory of a projectile. It has an initial velocity of magnitude  $v$ , at an angle of  $\theta$  degrees from the positive x-axis direction.

The full trajectory, from launch to landing, of a projectile is determined by the magnitude and direction of the initial velocity. At all time instances, the trajectory is described by the horizontal position  $x$  and vertical position  $y$  of the projectile. Therefore, the  $x$  and  $y$  positions, in terms of  $v$  and  $\theta$ , are the following:

$$x = (v \cos \theta)t \quad (2.5)$$

$$y = (v \sin \theta)t - \frac{1}{2}gt^2 \quad (2.6)$$



Total horizontal distance traveled by the projectile, before it arrives on the ground, known as *range* of the projectile,  $r$ , total time,  $T$ , and maximum height,  $H$ , are some of the special characteristics of projectiles. They are given by,

$$r = \frac{v^2 \sin 2\theta}{g} \quad (2.7)$$

$$T = \frac{2v \sin \theta}{g} \quad (2.8)$$

$$H = \frac{(v \sin \theta)^2}{2g} \quad (2.9)$$

The MLPQ system requires the constraints to be linear inequalities [3][4][5]. In Equations 2.5 and 2.6,  $x$  is linear in terms of the variables  $v$  and  $t$ , but they are non-linear in terms of  $\theta$ . In Equation 2.5, the variable  $y$  is linear in terms of  $v$ , but it is non-linear in terms of  $\theta$  and  $t$ . One possible way to minimize the non-linearity problem of  $x$  and  $y$  over  $\theta$  is to have different databases for different specific angles in MLPQ system.

In Equation 2.6, it can be seen that  $y$  is not a linear function of  $t$ . But it is possible to approximate it into a linear inequality in  $t$ , i.e., take several values of  $t$  (that span throughout the trajectory) and their corresponding  $y$  values, then use a *linear piece-wise approximation* method to get a linear function of  $t$  [6]. At this point, Equations 2.5 and 2.6 are ready to be used for the design of a database for representing a projectile motion.

Moving objects constraint database representations for projectiles launched at  $30^\circ$ ,  $45^\circ$  and  $60^\circ$  and  $100m/s$  have been implemented in the MLPQ System. The database design for the projectiles is shown in Figure. 2.3.

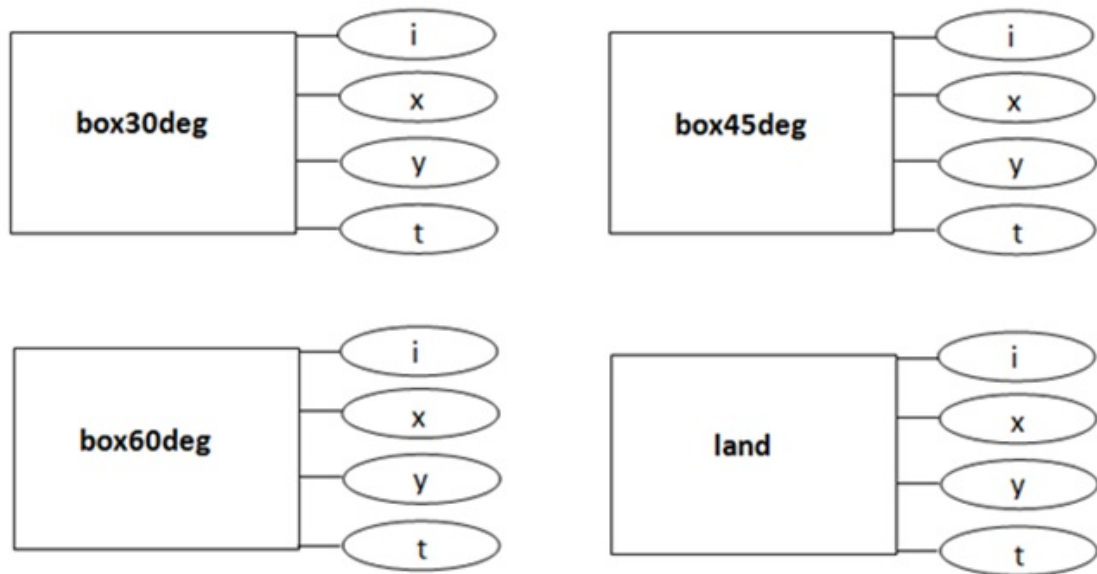


FIGURE 2.3: Constraint database design for three projectiles and a land. The *box30deg* design represents the constraint database for a projectile launched at  $30^\circ$ . Similarly, the *box45deg* and the *box60deg* projectiles represent for projectiles launched at  $45^\circ$  and  $60^\circ$ , respectively. Finally, *land* is a constraint database for the ground level

## 2.3 Result and Analysis

The snippet of a moving object constraint database input for the MLPQ system, whose database design is depicted in Figure 2.3, is given in Figure 2.4.

```

projectile - Notepad
File Edit Format View Help
land(id,x,y,t):-
x>=0,
x<=1100,
y>=0,
y<=10,
t>=0,
t<=18.

```

(A)

```

projectile - Notepad
File Edit Format View Help

begin%MLPQ%

box30deg(id,x,y,t) :-
id = 1,
x >= 0,
x <= 15,
y >= 10,
y <= 25, t >= 0, t <= 1.

box30deg(id,x,y,t):-
id = 1,
x - 86.6t >= 0,
x - 86.6t <= 15,
y-35.000000t>=20.000000,
y-35.000000t<=35.000000, t>=1, t<=2.

box30deg(id,x,y,t):-
id = 1,
x - 86.6t >= 0,
x - 86.6t <= 15,
y-25.000000t>=40.000000,
y-25.000000t<=55.000000, t>=2, t<=3.

box30deg(id,x,y,t):-
id = 1,
x - 86.6t >= 0,
x - 86.6t <= 15,
y-15.000000t>=70.000000,
y-15.000000t<=85.000000, t>=3, t<=4.

box30deg(id,x,y,t):-
id = 1,
x - 86.6t >= 0,
x - 86.6t <= 15,
y-5.000000t>=110.000000,

```

(B)

```

projectile - Notepad
File Edit Format View Help

box45deg(id,x,y,t) :-
id = 1,
x >= 0,
x <= 15,
y >= 10,
y <= 25, t >= 0, t <= 1.

box45deg(id,x,y,t) :-
id = 1,
x - 70.7t >= 0,
x - 70.7t <= 15,
y-55.700000t>=20.000000,
y-55.700000t<=35.000000, t>=1, t<=2.

box45deg(id,x,y,t) :-
id = 1,
x - 70.7t >= 0,
x - 70.7t <= 15,
y-45.700000t>=40.000000,
y-45.700000t<=55.000000, t>=2, t<=3.

box45deg(id,x,y,t) :-
id = 1,
x - 70.7t >= 0,
x - 70.7t <= 15,
y-35.700000t>=70.000000,
y-35.700000t<=85.000000, t>=3, t<=4.

```

(C)

```

projectile - Notepad
File Edit Format View Help

box45deg(id,x,y,t) :-
id = 1,
x >= 0,
x <= 15,
y >= 10,
y <= 25, t >= 0, t <= 1.

box45deg(id,x,y,t) :-
id = 1,
x - 70.7t >= 0,
x - 70.7t <= 15,
y-55.700000t>=20.000000,
y-55.700000t<=35.000000, t>=1, t<=2.

box45deg(id,x,y,t) :-
id = 1,
x - 70.7t >= 0,
x - 70.7t <= 15,
y-45.700000t>=40.000000,
y-45.700000t<=55.000000, t>=2, t<=3.

box45deg(id,x,y,t) :-
id = 1,
x - 70.7t >= 0,
x - 70.7t <= 15,
y-35.700000t>=70.000000,
y-35.700000t<=85.000000, t>=3, t<=4.

```

(D)

FIGURE 2.4: (A) Snippet of a geographical constraint database of the land that represents the ground on the projectile motion. (B) , (C) and (D) are snippets of a moving object constraint database that represent the projectile motions launched at 30, 45 and 60 degrees, respectively.

The projectiles are represented by moving object constraint databases. Before launch, i.e. time  $t = 0$ , the projectiles can be assumed of geographical databases representing  $15 \times 15$  square shape, located at the origin. After launch, they are moving object databases changing their position according to their projectile path.  $box30deg(i, x, y)$ ,  $box45deg(i, xy)$  and  $box60deg(i, x, y)$  are the moving object constraint databases representing the three projectiles launched at 30 , 45 and 60 degrees, respectively.

Figure 2.5 shows screen shot of the animation of the constraint database representing the projectiles and the ground in MLPQ system. The screen shots were taken at each step of MLPQ system animation. This means, multiple screen shots were taken, from the launch to the landing. All the screen shots were then compiled into one picture. Note that, all the screen shots are exactly the same except the projectiles are displaced in every next screen shot. Hence, when compiled into one picture, it appears each projectile to have a sequence of the same box in a projectile path.

It is also interesting to note that at the time of launch, i.e. when time  $t = 0$ , there is only one green colored box visible. During flight there are three (green, blue and yellow) boxes. After landing there are two boxes. There is reason related to the physics of the projectiles and how MLPQ system runs. It is discussed under the Discussion and Conclusion section.

Finally, to check the accuracy of the information stored in the constraint database, database query was made. The idea is to make a position query at a random time and compare the query result with a mathematical result from Equations 2.5 and 2.6. Hence, a query was made on the  $box30deg()$  constraint database, to find the position of the top-right corner point of the projectile after 3.5s. Note that, at the time  $t = 0s$ , the position of the top-right corner point is (15, 25). Figure 2.6 shows the query result, which is (318.100, 137.500). The result through mathematical calculation is (318.109, 139.975).

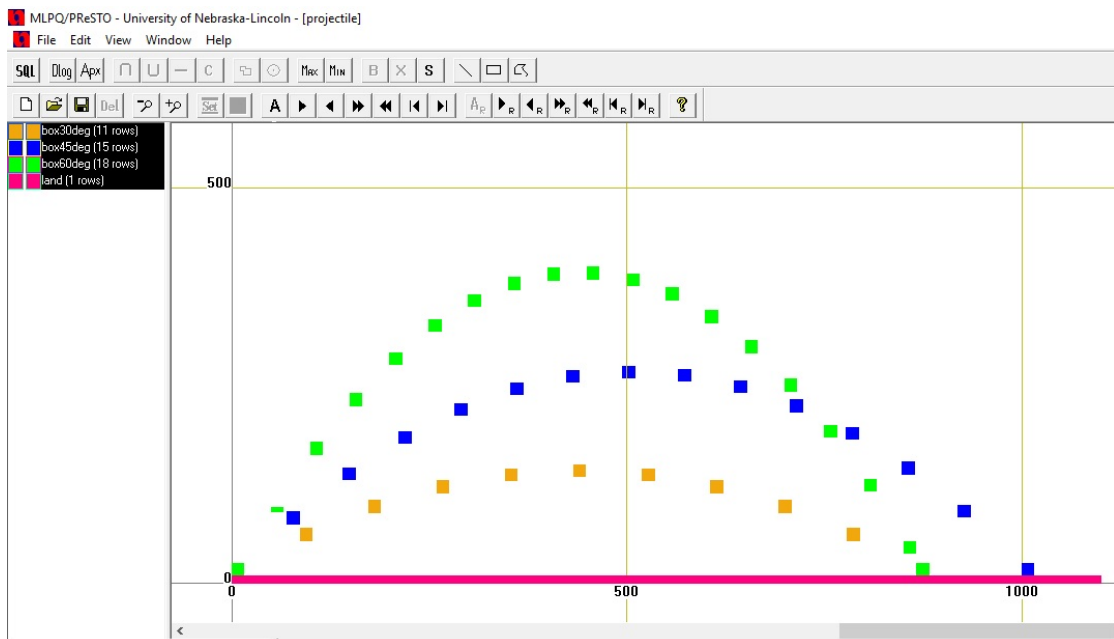


FIGURE 2.5: A compilation of the screen shots of the MLPQ system when running the constraint database of the projectiles and the ground. The projectiles are launched at  $x = 0$  and  $y = 0$ . The yellow, blue and green colored projectiles (boxes) are launched at  $30^\circ$ ,  $45^\circ$  and  $60^\circ$ , respectively. The pink region at the bottom represents the ground. On the left, *box30deg*, *box45deg*, *box60deg* and *land* are the constraint databases.

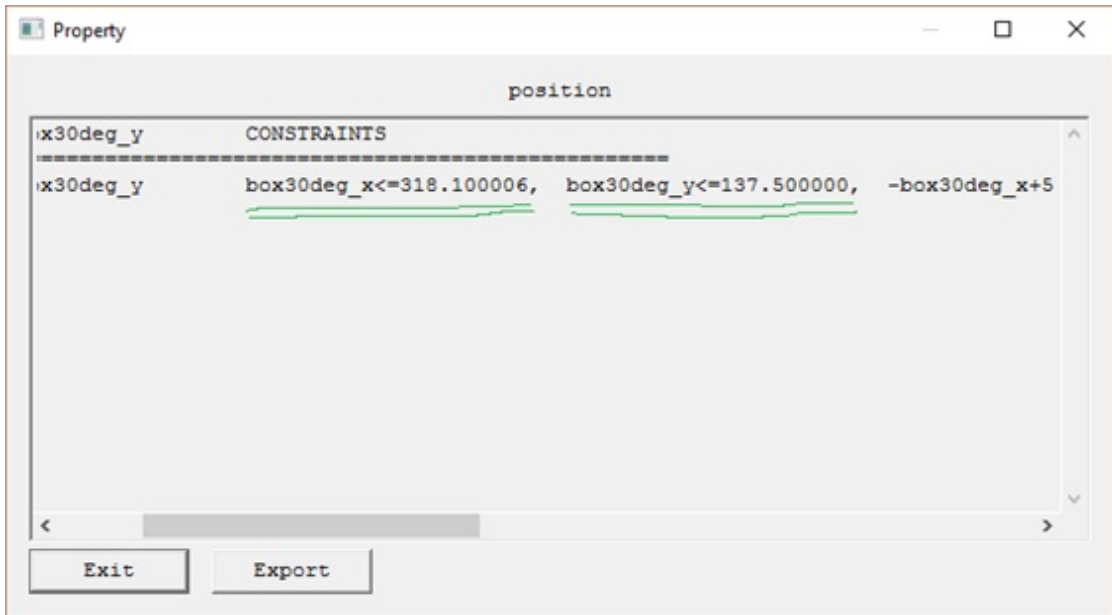


FIGURE 2.6: The query result that requests the position of the top-right corner of projectile launched at  $30^\circ$ , at time  $t = 3.5s$ . The underlined parts of the result belong to the top-right corner point.

## 2.4 Discussion and Conclusion

At the time of launch there is only one visible box, the green box, instead of the three boxes representing the three projectiles. The possible reason for that is that, MLPQ system reads from top to bottom on the input constraint database. Hence, it read the constraint database for the projectile launched at  $30^\circ$  first, then that of  $45^\circ$  launched projectile and finally that of the  $60^\circ$  degree launched projectile. They all start at the origin, and hence overlapping, which resulted in to show the color of the last read database, green.

After all the projectiles arrived, only two boxes are visible. This is because both the projectiles launched at the 30 degrees and 60 degrees have the same range, hence overlapping. This is to be expected, as per Equation 2.7, two projectiles launched at complementary angles (two angles whose sum is 90 degrees) have equal ranges. Since the

projectile launched at 60 degrees arrive later than the one launched at 30 degrees, the color of the overlap box is green. Moreover, according to Equation 2.7, the maximum range occurs at a launch angle of 45 degrees. This is consistent with the result in Figure 2.5, where the blue projectile traveled the farthest horizontally.

On arriving to the ground, the yellow (30° projectile), blue (45° projectile) and green (60° projectile) boxes arrived in that order. This is also consistent with Equation 2.8. The total time of flight increases with the increase of the launching angle (sine of an angle increases with the increase of the angle in the range  $[0, 90]$ ).

Maximum height of a projectile increases proportionally with the square of the sine of the launching angle, according to Equation 2.9. As can be seen in Figure 2.5, the maximum height of the three projectiles, in their angle of launch, is ranked, highest to lowest, 60°, 45° and 30°.

The accuracy of the result is not only relative to each other. For example, in calculating the range of the projectile launched at 45°, with initial speed of  $100m/s$ , the result is  $1000m$ , according to Equation 2.7. In Figure 2.5, the blue box (45° projectile) arrives  $1000m$  away from the origin.

As mentioned on the previous section, when querying the position of the projectile launched at 30°, its top-right corner point, the query result and the mathematical results were almost equal. The slight discrepancy on the  $y$  component may be attributed to the linear piecewise approximation performed on the  $y$  component of the position when implementing the database (there was no linear piecewise approximation on the  $x$  component, because it was linear). The goal of this chapter was to show that a projectile motion (which is accelerated motion) can be represented by a constraint database, using the MLPQ System. The variables of constraint databases need to be linear. Equations 2.5 and 2.6, which define the trajectory of projectile, have non-linear variables. By



constructing database for specific angles and by approximating the quadratic dependence of position on time into a linear dependence, using linear piecewise approximation, this chapter showed that it is possible to represent projectile motion in constraint database.

## Chapter 3

# Constraint Database Representation of Inclined Plane in MLPQ System

Inclined plane problem is a physics problem that applies Newton's second law[1]. As projectile motion is a common problem in two dimensional motion problems in physics, inclined plane problem is a common problem in the application of Newton's second law. There are several problems in physics textbooks that stem from the inclined plane model, with or without friction. Here the focus is on frictionless inclined plane problem. In projectile motion, the motion is affected only by gravity. In inclined plane problem, however, there is additional *normal force* involved ( assuming frictional force is ignored, as is the case here)[1]. The textbooks solve the problem using Newton's second law, that relates the net force applied to the acceleration of an object, mathematically. In this chapter, however, it is tried to represent an inclined plane problem using constraint database in MLPQ system.

### 3.1 Background – Incline Plane Problem

Any tilted surface upon which an object can slide up or down can be considered an inclined plane. A slide at a park, interstate exit ramp, truck loading ramp are all examples of inclined planes. Figure 3.1 shows a diagrammatical illustration of an inclined plane. Note that the quantities of the lengths used are random. Moreover, the units of the lengths do not impact the quantity of the result, as long as that the unit of the result

is consistent with the unit of the lengths used (all the lengths need to have the same unit too).

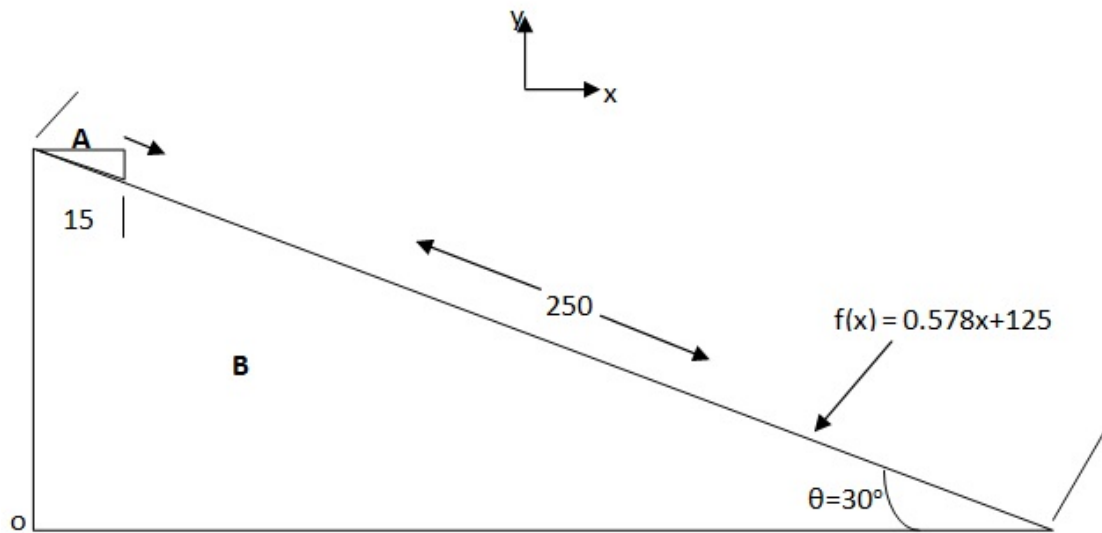
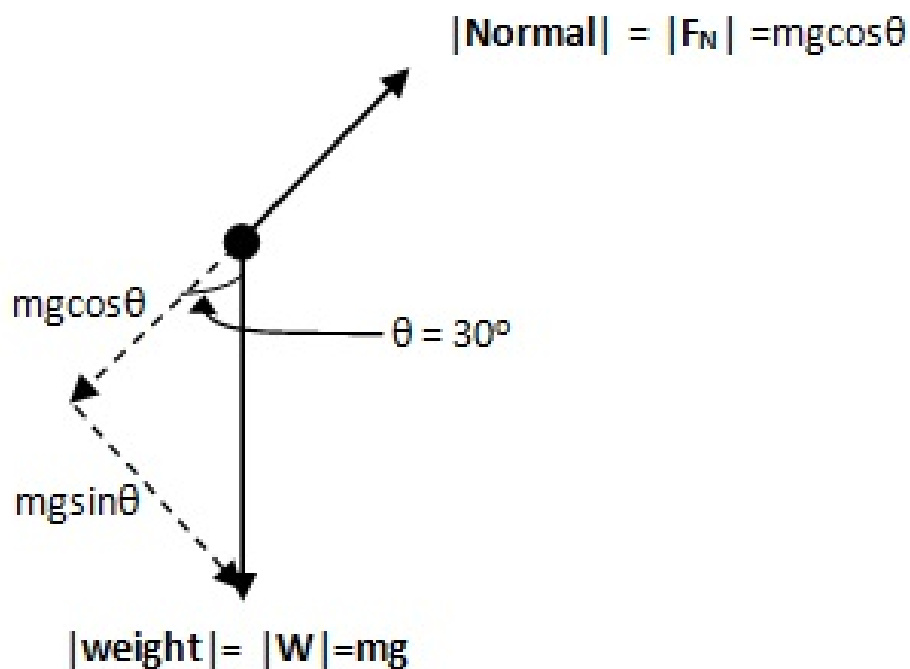


FIGURE 3.1: Diagrammatical illustration of an inclined plane. The triangular block **A** slides on the tilted surface of block **B**. The tilted surface of block **B** is the inclined plane in the figure. Assumptions made on the figure are: the horizontal thickness of block **A** to be 15unit, the distance of the inclined plane to be 250units, the tilt angle of the incline to be  $30^\circ$  and the right angle of block **B** to coincide on the origin of a Cartesian coordinate.

Drawing *free-body diagram* of an object is very important method in analyzing the motion of the object when Newton's second law is taken into consideration. Free-body diagram of an object is a diagrammatical representation of an object as a particle and the forces acting on the object as arrows (the direction of an arrow represents the direction of the force while the length of the arrow represents the magnitude of the force) [2]. The forces that do not act on the object under consideration are excluded, helping focusing on the object exclusively. Free-body diagram of block **A** from Figure 3.1 is shown in Figure 3.2.




---

FIGURE 3.2: Free-body diagram of block **A** in Figure 3.1.  $\mathbf{W}$  is the gravitational force (weight) on block **A**.  $\mathbf{F}_N$  is the force of normal on block **A** by the inclined plane. The mass of block **A** is given by  $m$ .

As can be seen on Figure 3.2, block **A** of Figure 3.1 experiences only two forces, namely, the gravitational force,  $\mathbf{W}$ , commonly known as weight (mass of block **A** is  $m$  and the magnitude of the gravitational acceleration is  $g$ ), and the force of normal,  $\mathbf{F}_N$ . Normal is a contact force exerted by a surface (any object, for that matter) on an object [2]. Normal is perpendicular to the surface [2]. For convenience, in Figure 3.2, weight is resolved into two component forces, parallel to the surface and perpendicular to the surface. According to Newton's second law, the net force parallel to the surface is equal to the product of the mass and acceleration of the sliding object [2]. Hence,

$$mg \sin \theta = ma \quad (3.1a)$$

$$g \sin \theta = a \quad (3.1b)$$

where,  $a$  is the magnitude of the acceleration of block **A** on the surface of the block **B**.

Therefore, the magnitude of the acceleration of block **A** on the surface of the inclined plane (block **B**) is given by Equation 3.1. It is assumed to start from rest at the top of the inclined plane accelerating down, parallel to the surface. The position of block **A**, at any time  $t$ , using Equation 2.4, is then given by,

$$x = \left(\frac{1}{2}(g \sin \theta)t^2\right) \cos \theta \quad (3.2)$$

$$y = \left(250 - \frac{1}{2}(g \sin \theta)t^2\right) \sin \theta \quad (3.3)$$

Note that in both Equations 3.2 and 3.3,  $\theta = 30^\circ$ .

### 3.2 Implementation of Constraint Database - Inclined Plane

The goal here is to be able to represent blocks **A** and **B** in Figure 3.1, using constraint database in MLPQ system. Since block **A** is a moving object, it is represented by a moving object constraint database. However, block **B** does not move, hence it is represented with a geographical constraint database.

In defining the constraints for the blocks, it is important to first find the equation of the line that represents the inclined plane. And it is given by,

$$y = 0.578x + 125 \quad (3.4)$$

As mentioned in the previous chapter, MLPQ system requires its constraint database variables to be linear [3][4][5]. Therefore, Equation 3.4 is important in describing  $y$ , in terms of a linear variable  $x$ .

Now it can be seen block B to be bounded in,

$$\begin{cases} x \geq 0, & x \leq 250 \cos \theta \\ y \leq 0.578x + 125 \end{cases} \quad (3.5)$$

and block A is bounded by,

$$\begin{cases} x \geq T, & x \leq T + 15 \\ y \geq 0.578x + 125 \\ \text{where} & T = (\frac{1}{2}(g \sin 30^\circ)t^2) \cos 30^\circ \end{cases} \quad (3.6)$$

In Equation 3.6,  $T$  is not linear in  $t$ . Therefore, *linear piecewise approximation* is used to convert it into linear inequality [6].

The design of the database is given in Figure 3.3.

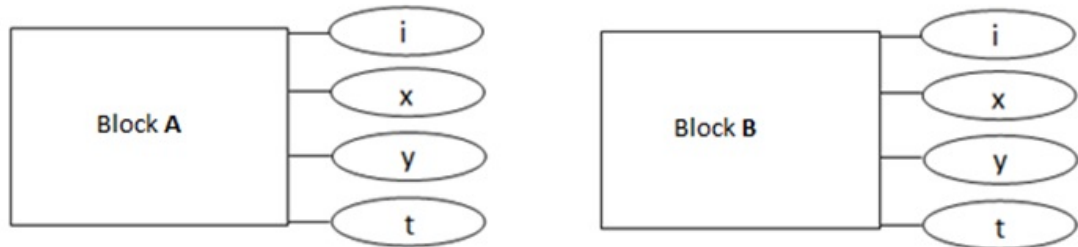
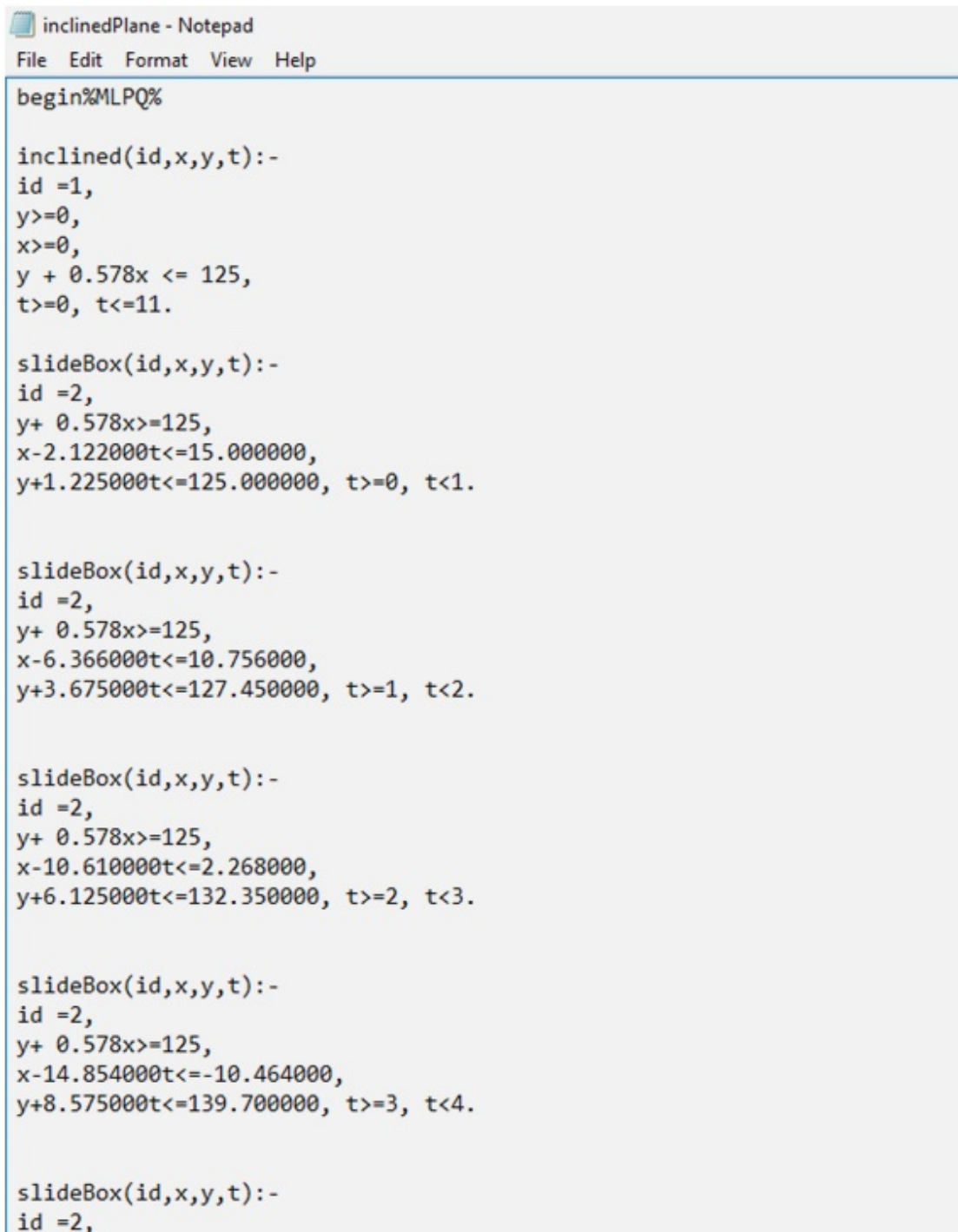


FIGURE 3.3: The design of the constraint databases for blocks A and B.

### 3.3 Result and Analysis

Block A takes about 10s to cover the 250m long inclined plane (assuming all units are SI units). Therefore, the non-linear inequalities in Equation 3.6 are approximated into linear inequalities (using linear piecewise approximation) in the time range of 0 to 11 s.

The snippet of the input of constraint database in MLPQ system for the blocks is shown in Figure 3.4.



```

inclinedPlane - Notepad
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begin%MLPQ%

inclined(id,x,y,t):-
id =1,
y>=0,
x>=0,
y + 0.578x <= 125,
t>=0, t<=11.

slideBox(id,x,y,t):-
id =2,
y+ 0.578x>=125,
x-2.122000t<=15.000000,
y+1.225000t<=125.000000, t>=0, t<1.

slideBox(id,x,y,t):-
id =2,
y+ 0.578x>=125,
x-6.366000t<=10.756000,
y+3.675000t<=127.450000, t>=1, t<2.

slideBox(id,x,y,t):-
id =2,
y+ 0.578x>=125,
x-10.610000t<=2.268000,
y+6.125000t<=132.350000, t>=2, t<3.

slideBox(id,x,y,t):-
id =2,
y+ 0.578x>=125,
x-14.854000t<=-10.464000,
y+8.575000t<=139.700000, t>=3, t<4.

slideBox(id,x,y,t):-
id =2,

```

---

FIGURE 3.4: Constraint database input of MLPQ system for blocks **A** and **B**.  $inclined(id, x, y, t)$  is the constraint database for block **B** and  $slideBox(id, x, y, t)$  is constraint database for block **A**.



A series of screen shots of the animation of the constraint database, in MLPQ system, is shown in Figure 3.5. The time interval at which the screen shots were taken is constant, 2 steps each. There are about 10 total steps for block A to slide from top to bottom.

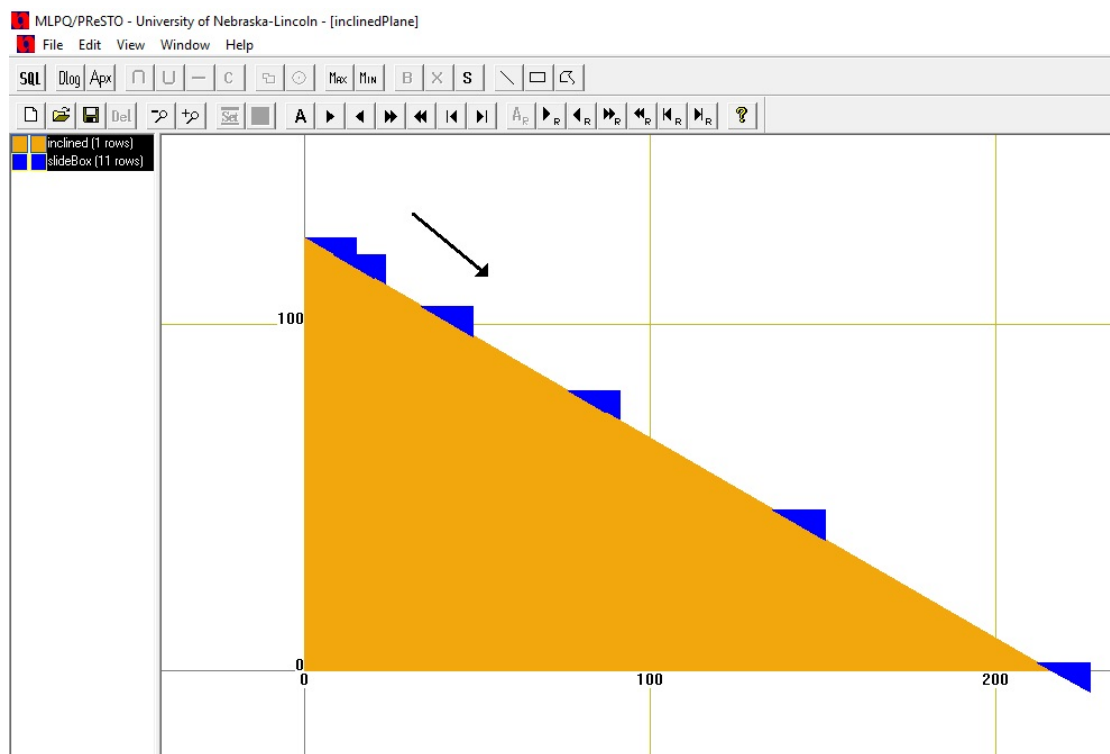


FIGURE 3.5: A series of screen shots of block A sliding on block B (inclined plane). The arrow indicates the direction of slide. The screen shots are taken at equal time intervals.

Since the only thing moving in the system of the inclined plane is block A, finding the position of the block at some given time gives good information about the state of the system. Therefore, a query of the position of block A is made on the constraint database in MLPQ system. The query requests the position ( $x$  and  $y$  coordinates) of block A at time  $t = 3.5s$ , which is a random time. Figure 3.6 shows the query result.

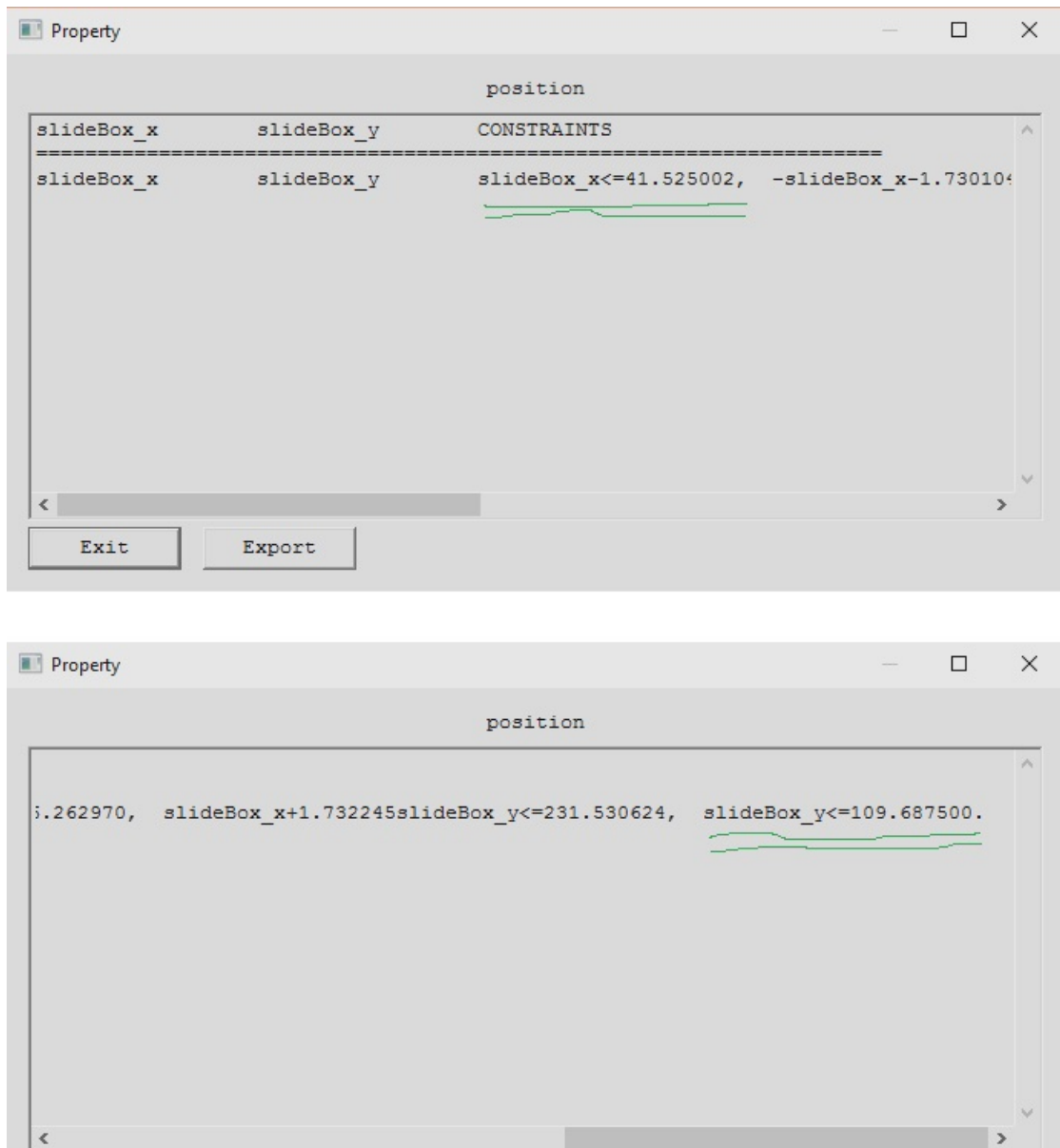


FIGURE 3.6: Query result of the position of block A at time  $t = 3.5s$ . The top and bottom panes are the same, except the bottom pane is scrolled to the right end. The two underlined parts of the result define the top-right corner point at block A.

The two underlined parts of the result define a point at the top-right corner of block A. Hence, according to the result of the query, the position of that point is  $(41.525, 109.688)$ . Theoretically, the position of the same point can be calculated using Equations 3.2 and 3.3. Using those equations, the position of the point is  $(40.992, 109.994)$ .

### 3.4 Discussion and Conclusion

In Figure 3.5, the screen shots are taken at equal time interval, 2 steps each (in SI unit a step may represent 1 second). However, it is important to note that the distance covered in between each screen shot is not equal. It increases in each successive interval. This has physical significance. It implies that the block was accelerating when it was sliding down.

From Figure 3.5 it is possible to learn that the block accelerates when sliding down. However, it is not easy to guess where block A is going to be after a certain time. Therefore, accuracy of query result on the constraint database is important. Hence, comparison of the result of a query of a position of block A (a specific reference point at the block) with the position of the same point obtained using Equations 3.2 and 3.3 is made. As mentioned in the previous section, the result of query and calculation of the position of the top-right corner of block A are (41.525, 109.688) and (40.992, 109.994), respectively. The results are very close. The slight difference may be attributed to the approximation of non-linear inequalities to linear inequalities, using piecewise linear approximation.

The goal of this chapter was to show the possibility of representing a frictionless inclined plane problem (which is an accelerated motion), using constraint database in MLPQ system. The equations of the position of a sliding object are not linear in time (because of acceleration), as can be seen in Equations 3.2 and 3.3. However, it is possible to circumvent this challenge by approximating the equations using linear piecewise approximation method. Therefore, it is possible to represent a frictionless inclined plane, at a specified angle, on a constraint database in MLPQ system.

## Chapter 4

# Constraint Database Representation of Sea Turtle in MLPQ System

Dr. Kenneth Lohmann, *et al.*, worked on tracing the migration of loggerhead and green turtles [7]. The study area is in North Carolina, USA. However, the turtles migrate deep into the Atlantic ocean. The visualization of turtle migration using constraint database in MLPQ system, presented under this chapter, is based on the data obtained by Dr. Kenneth Lohmann, *et al* [7].

### 4.1 Background

Animal migration is one of the most observed phenomenon in biology, probably, in no small part, because movement itself is a defining characteristic of animals [7]. In his book, Archie Carr, professor of zoology at the University of Florida, first published in 1956 and titled *The Windward Road*, mentions an incident regarding sea turtles told to him by a captain of turtle fishermen's boat in Cayman Islands. According to the captain, a boat filled with sea turtles captured in their feeding area around northern Nicaragua, was shipped to Florida. Around the coast of Florida the boat capsized. The turtles were marked, customarily with the fishermen's initials, and to the surprise of the fishermen the turtles got back to where they were captured initially [8].

Dr. Lohmann, *et al*, have been interested on the migration of juvenile loggerhead

(*Caretta caretta*) and green (*Chelonia mydas*) sea turtles [9]. These juvenile turtles originate from the east coast of the USA [9]. They show strong homing behavior, i.e., they return back to their feeding sites after migration [9]. They have also studied hatchling turtles.

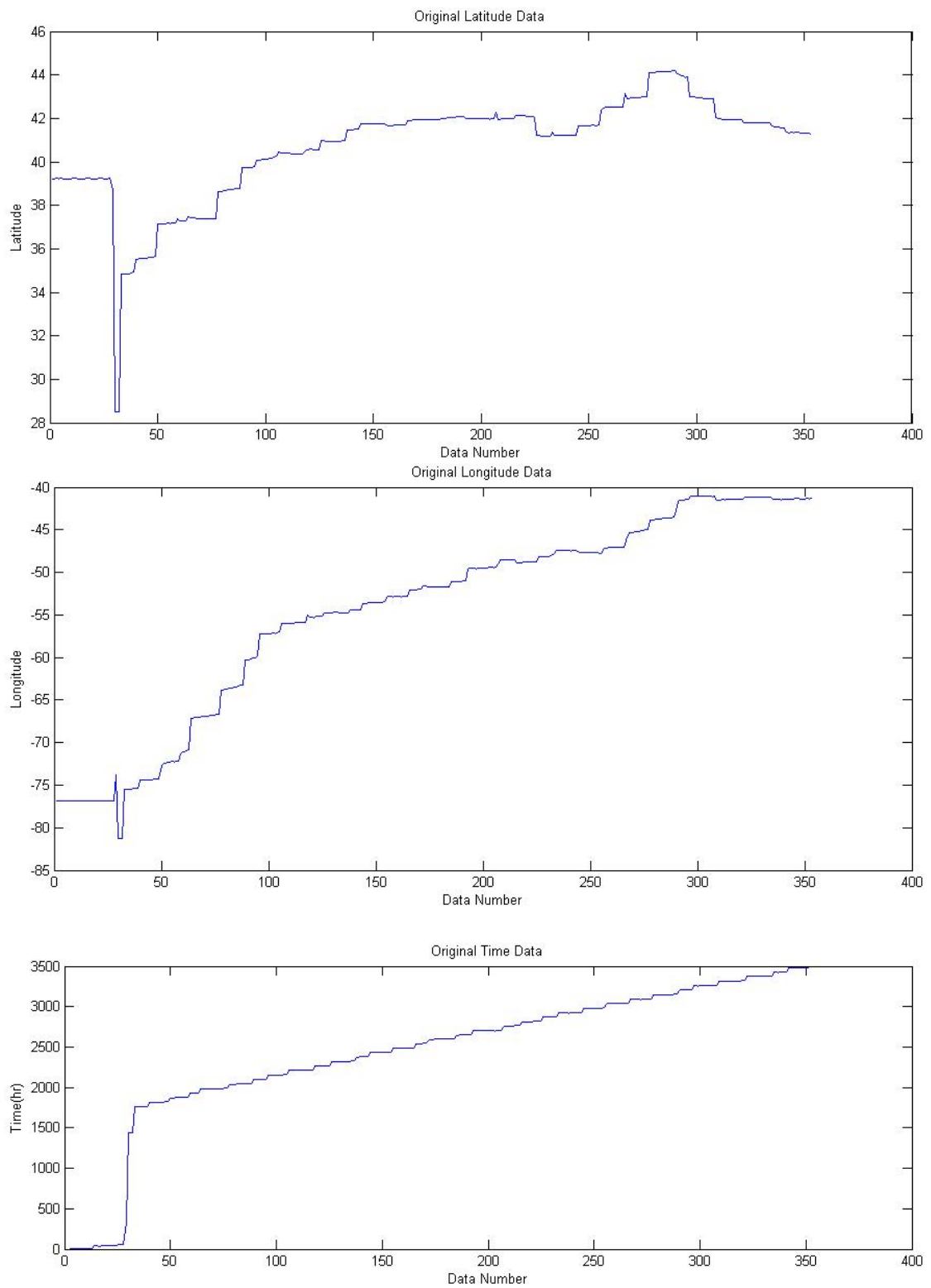
In courtesy of Dr. Lohmann, here some data of sea turtle location and time in their migration in the Atlantic ocean is represented in constraint database in the MLPQ system for visualization purpose.

## 4.2 Analysis of the Original Data

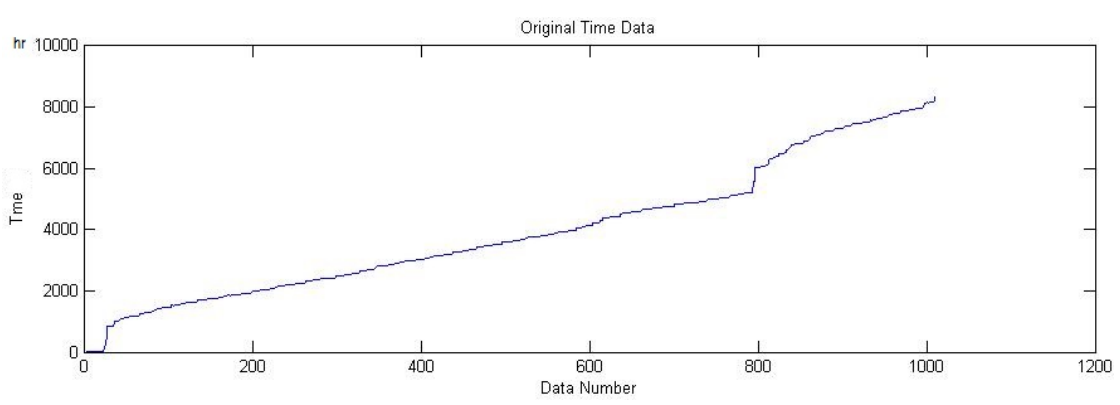
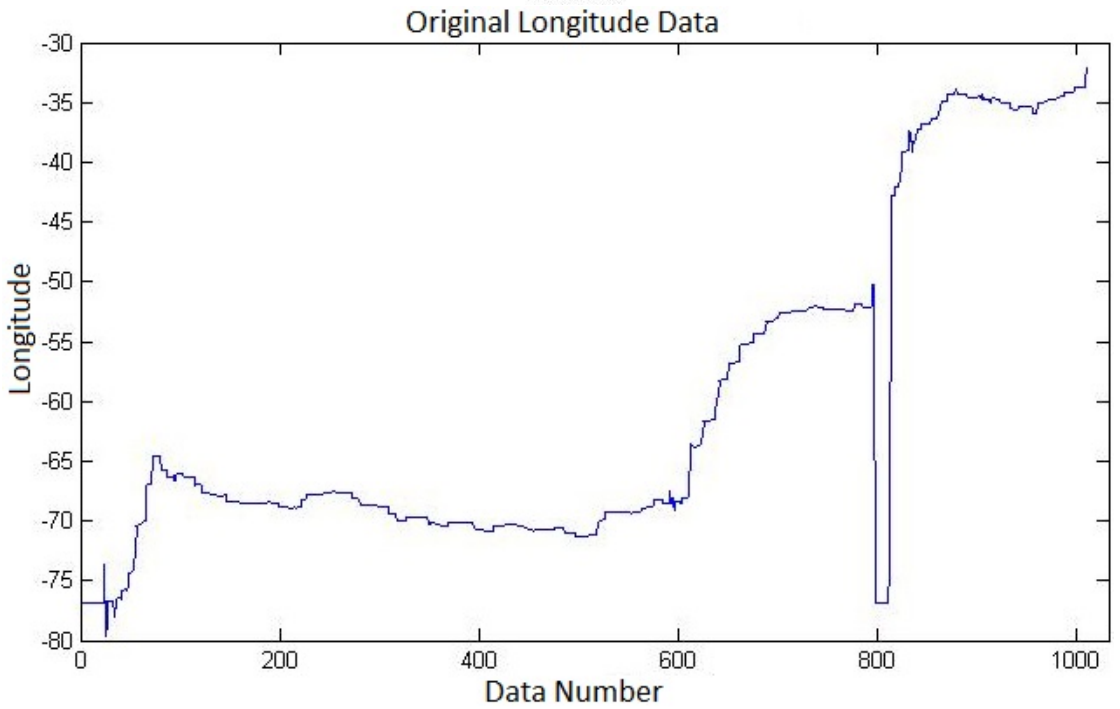
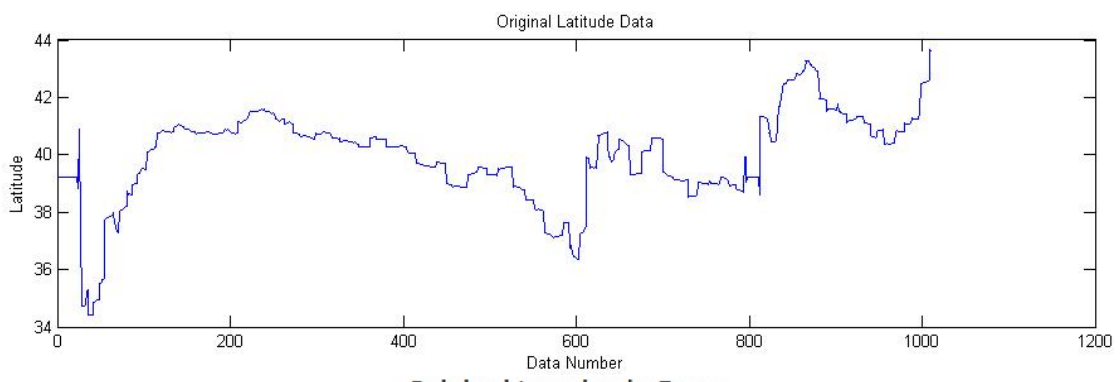
The data used are the latitude and longitude of the boundaries of the US states (and the geographical span of the United States) from [10] and [11], and the tracked location of three sea turtles during their migration in the Atlantic ocean, in latitude and longitude. The United States map is used to give a perspective of the movement of the sea turtles relative to the US coast in the Atlantic ocean.

The data from Dr. Lohmann includes the location of three sea turtles tracked over the time the turtles navigate the Atlantic ocean. For convenience, the three turtles are named here as, Dexter, Irving and Nala. The turtles were tracked at different times. A location of a turtle is specified by the latitude and longitude coordinate of the turtle. An electronic device is attached to a sea turtle. This device communicates with a satellite and feeds back the location of the turtle to a device at a data collecting station [9].

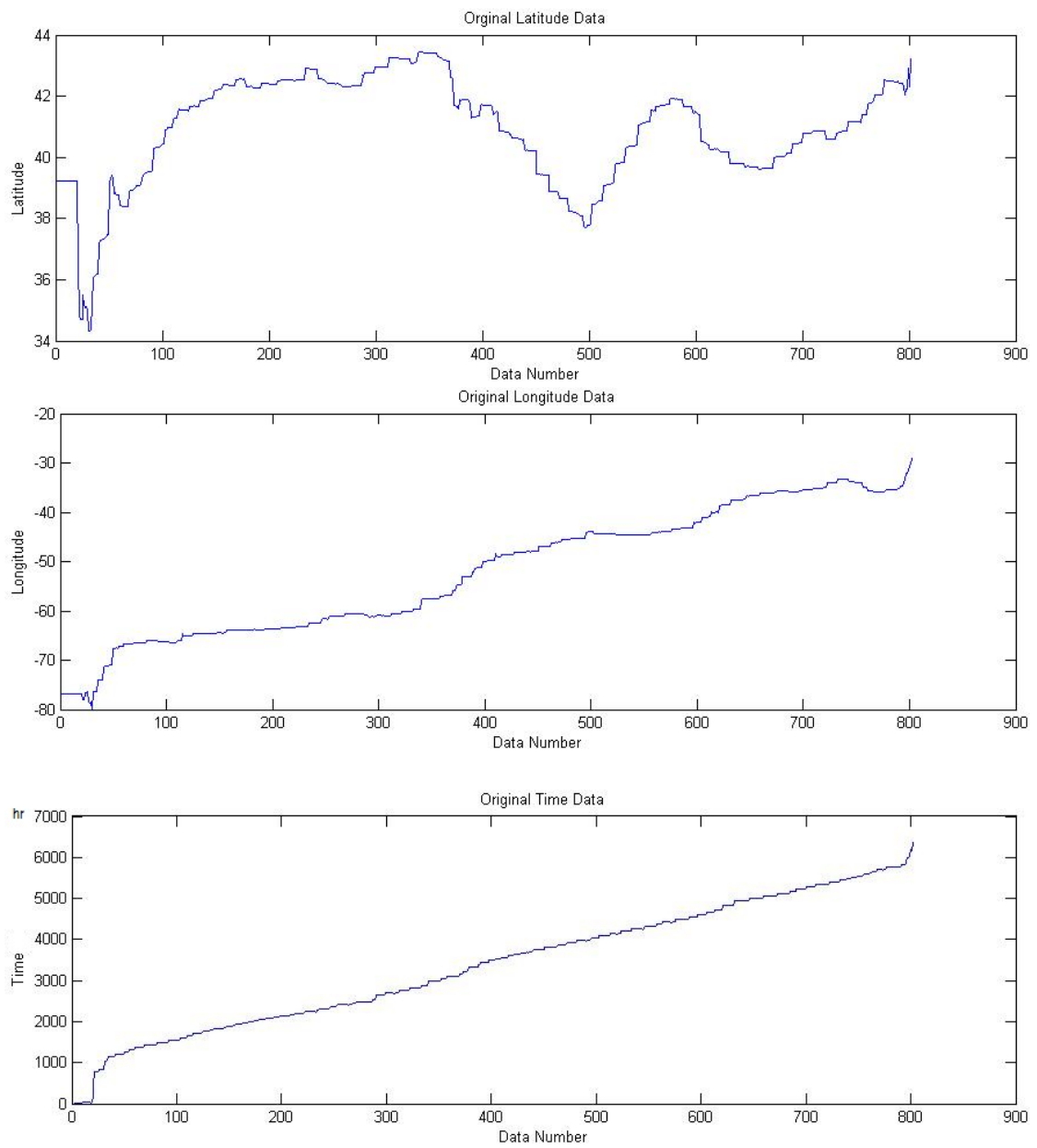
The data of the sea turtle migration is subject to some irregularities. The source or cause of the irregularities of the data are not of focus here, but it is important to minimize them. The original data is shown in Figure 4.1.



(A) Dexter's Original Data



(B) Irving's Original Data



(C) Nala's Original Data

---

FIGURE 4.1: The original data of sea turtles describing their positions in latitude and longitude, and duration in hours (since recording started) .

The time was recorded in a date format as "yyyy/mm/dd hh:MM." A Java program

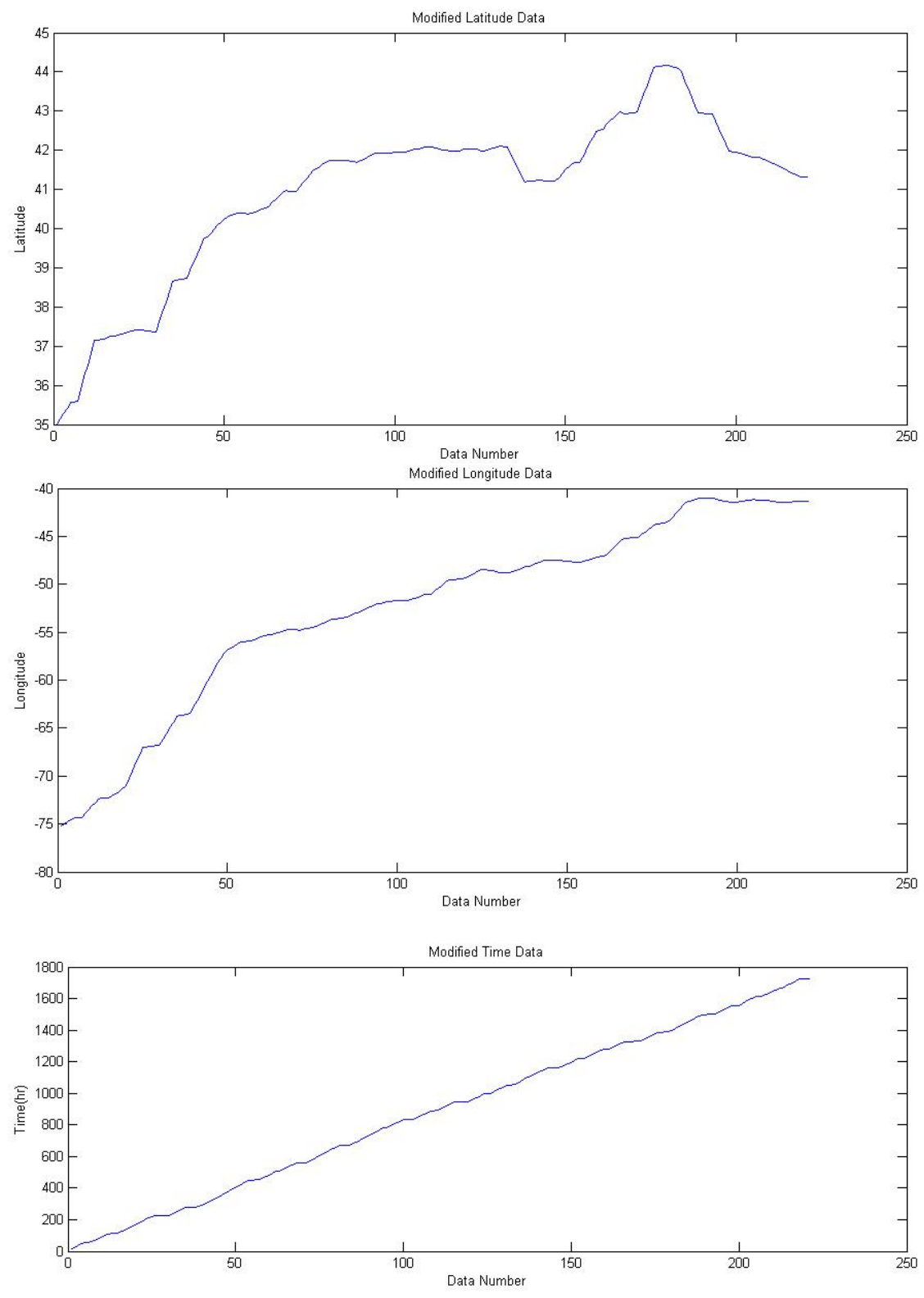


is used to convert it into duration of time in hours from the start of recording. The irregularity of the original data of time is not hard to see in Figure 4.1. Time should increase linearly. In Figure 4.1(B), for example, the time is more or less linear except around data point 800. It can be seen the time graph jumps up vertically. Time data taken at a regular pace, which is what almost all time counters do, cannot jump instantly. Therefore it is fair to assume the time data at this point is aberrant.

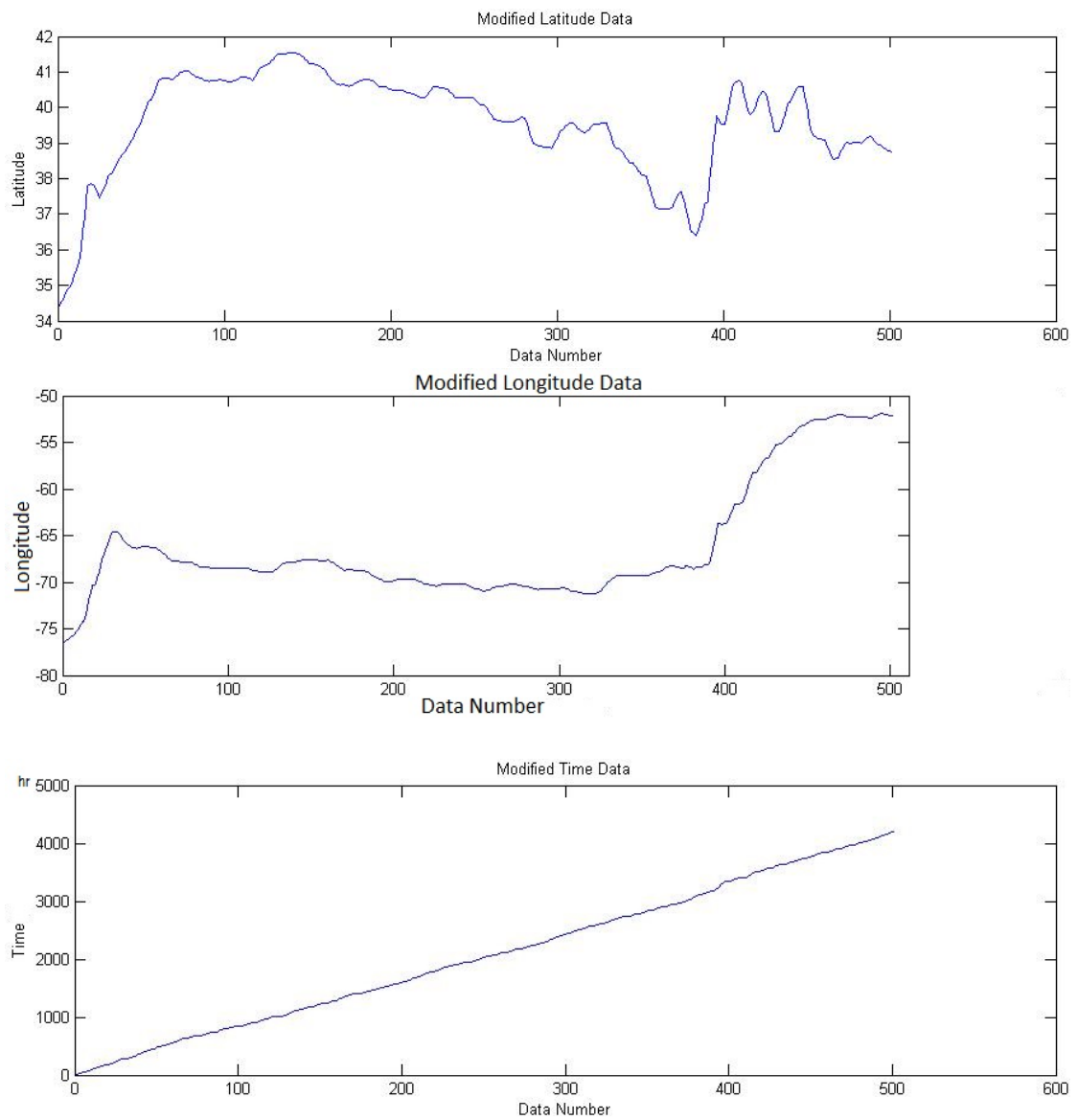
Similarly, the graphs of location, both longitude and latitude, show some vertical lines. Vertical line on those graphs would mean that the turtle is at two different latitudes, or longitudes, at the same time. That is not possible, hence, the location data points at which the location graphs have vertical slope indicate aberrant data.

### 4.3 Minimizing Data Aberration

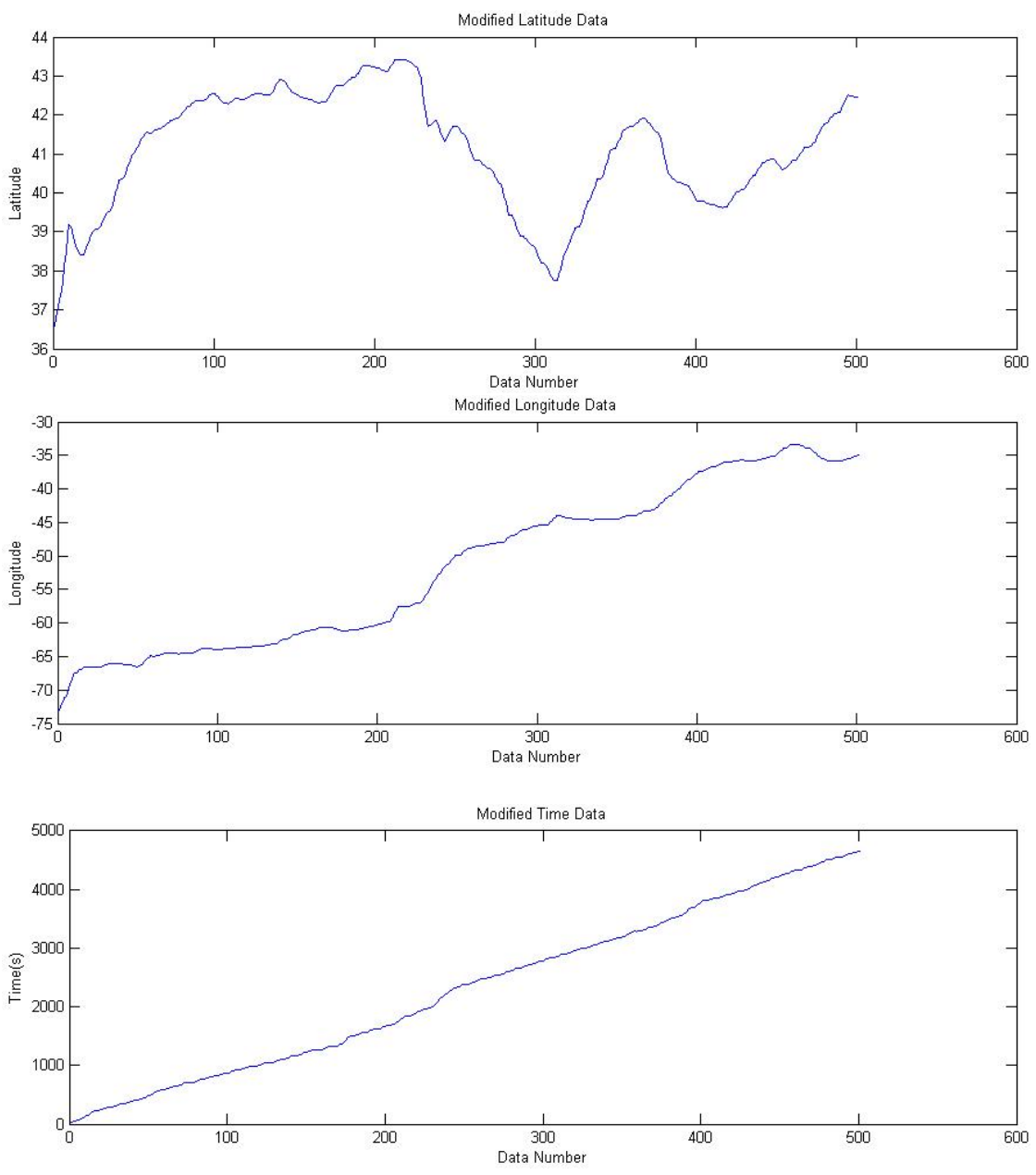
The aberrant data points on the original data cause the visualization of the migration of the sea turtles, in the Atlantic ocean, using the MLPQ system ( on any system for that matter), to be discontinuous and unrealistic. Without changing the general essence of the original data, the data irregularities can be minimized. One way to do that is to smooth out the deviant data points. Here, for the purpose of smoothing the data, each data point was replaced by the average of the five neighboring data points. Moreover, the data from the beginning and end of the data recording were trimmed out so as to focus on the steady data. The smoothing and trimming of the data was done using a Java program. Figure 4.2, shows the smoothed out trimmed out version of the original data in Figure 4.1.



(A) Dexter's Modified Data



(B) Irving's Modified Data



(C) Nala's Modified Data

FIGURE 4.2: The modified data of sea turtles describing their positions in latitude and longitude, and duration in hours (since recording started)

## 4.4 Implementation of Constraint Database

At this point, the data is raw data with its irregularities minimized. However, in order to be able to visualize the sea turtles movement through the Atlantic ocean, using the MLPQ system, it is necessary to represent the data in the form of constraint database. As afore mentioned, the constraint equations must be linear.

In order to help visualize the sea turtles' location, in the Atlantic ocean, in relation to the US land mass, the latitude and longitude data of boundaries of all states from [10] and [11] was converted into geographical constraint database of MLPQ system. A Matlab program, which is a slight modification (in order to adopt it to this particular purpose) of a Matlab program provided by Professor Revesz (University of Nebraska - Lincoln), is used to convert raw data from [10] and [11] into geographical constraint database of MLPQ system. A snippet of the geographical constraint database is given in Figure 4.3.



```

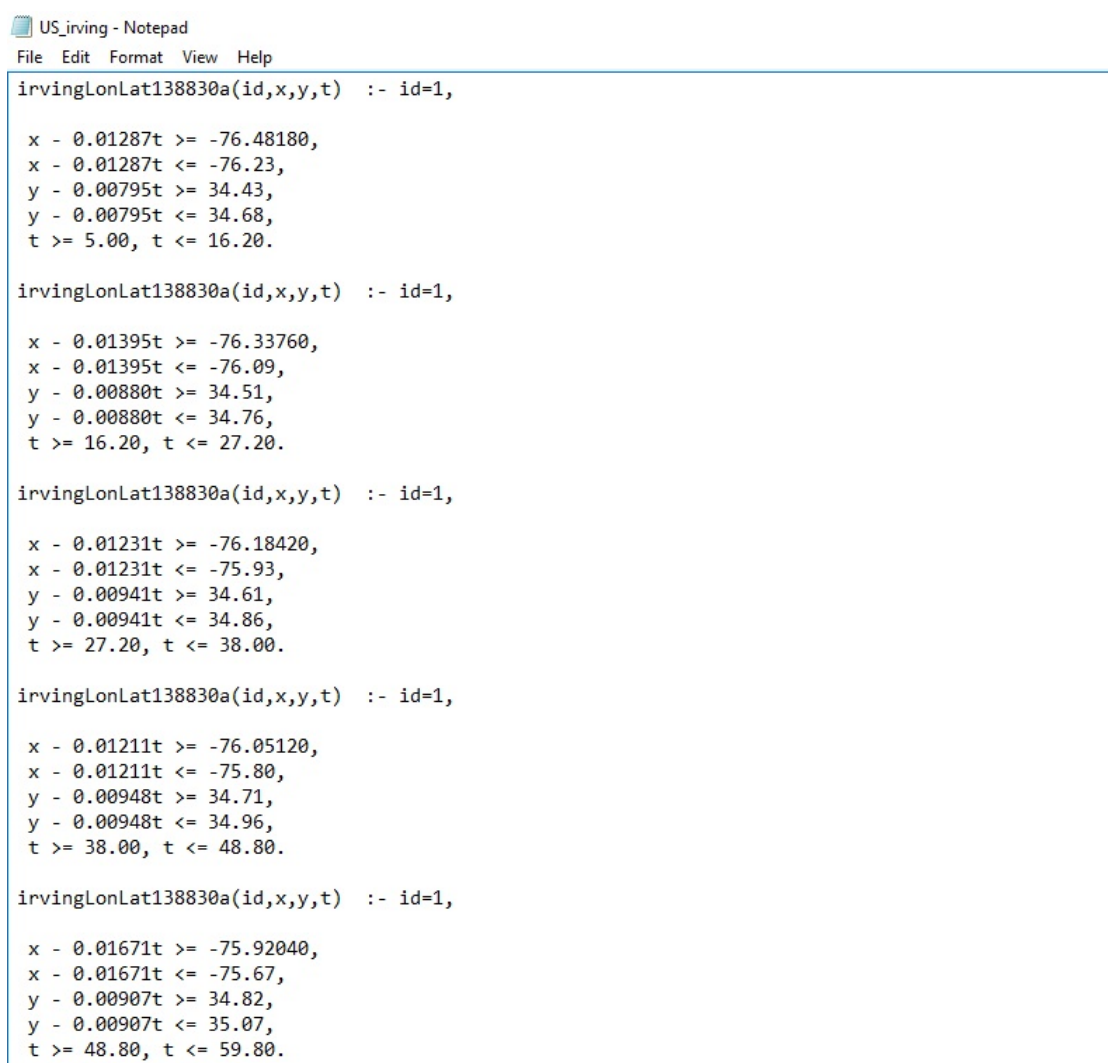
US - Notepad
File Edit Format View Help
NorthDakota(id,x,y) :- id=18, y+4.457952468x=-384.85639140766477, y+13.06442577x=-1217.9440728289328, y+3.407521368x=-282.83222034187486.
NorthDakota(id,x,y) :- id=19, y+0.001404212638x=45.798399257773312, y+3.162548765x=-259.46416280884625, y-0.09923000497x=-56.268846174863441.
NorthDakota(id,x,y) :- id=20, y-23.97561x=2367.4498780481158, y+6.145786x=-547.9879567197197, y+13.06442577x=-1217.944072828933.

Nebraska(id,x,y) :- id=1, y-0.07734876x=50.327023896365475, y+0.1101804124x=32.098644394330428, y-0.1974417165x=62.095893336084188.
Nebraska(id,x,y) :- id=2, y+1.131446x=-67.092593731039589, y+2.406721241x=-189.64502317960065, y+3.353603604x=-280.41951058558016.
Nebraska(id,x,y) :- id=3, y-2.305825x=265.60182864075534, y+0.09615385x=33.356151923070385, y+1.044061x=-58.365364176255099.
Nebraska(id,x,y) :- id=4, y+0.5683183x=-12.356307732735637, y+1.044061x=-58.365364176255099, y+0.4523809524x=-1.1131309523818729.
Nebraska(id,x,y) :- id=5, y+1.670854x=-118.74633065326255, y+20.70833333x=-1948.407983332065, y-4.380794702x=462.6271139737684.
Nebraska(id,x,y) :- id=6, y+2.173796x=-167.26116408477745, y+0.3323169x=10.180609684698609, y+0.5839300758x=-14.476979570345271.
Nebraska(id,x,y) :- id=7, y+1.830853563x=-134.23565896634256, y+3.353603604x=-280.41951058558016, y+38.70909091x=-3669.8334054463373.
Nebraska(id,x,y) :- id=8, y+1.488619x=-101.23200182094594, y+2.793494x=-226.81338613860763, y+20.70833333x=-1948.4079833320648.
Nebraska(id,x,y) :- id=9, y+3.323615x=-277.5446174928191, y+12.07273x=-1116.2931236368147, y-12.3252x=1222.1192081304612.
Nebraska(id,x,y) :- id=10, y+0.717973005x=-26.980558205067581, y+1.206921413x=-74.094795602019175, y+0.4788434x=-3.7364711565584514.
Nebraska(id,x,y) :- id=11, y+0.9286771x=-48.512180822727515, y-0.04835762148x=44.938261421676636, y+0.00062132169102x=39.939810335004935.
Nebraska(id,x,y) :- id=12, y+0.9629612x=-51.621275131781204, y-0.6772147x=109.11268824821668, y-0.1096529x=51.19340637449551.
Nebraska(id,x,y) :- id=13, y+0.001048061x=40.89364473723618, y+0.9971552628x=-60.759692858212794, x=-104.054300.
Nebraska(id,x,y) :- id=14, y+0.5897959x=-15.05182408166961, y+0.3149918x=11.91883344316388, y+0.4046615x=3.0909835738065468.
Nebraska(id,x,y) :- id=15, y-0.1096529x=-51.19340637449551, y-0.04835762148x=44.938261421676636, y+1.783495692x=-130.26440424506171.
Nebraska(id,x,y) :- id=16, y+0.3088128x=-12.809575455206282, y+0.4523809524x=-1.1131309523818729, y+0.7087126138x=-25.9163208062431.
Nebraska(id,x,y) :- id=17, y+0.6818811x=-23.357152697096787, y-5.569536x=579.39701854290433, y+0.275x=-15.96208249999706.
Nebraska(id,x,y) :- id=18, y+0.1101804124x=32.098644394330428, y+0.278974359x=-15.691383282051756, y-0.1750433276x=-59.91175251300141.
Nebraska(id,x,y) :- id=19, y+0.6465061656x=-19.938675866119091, y+0.2268314x=-20.759828067078594, y+0.4788434x=-3.7364711565584514.
Nebraska(id,x,y) :- id=20, y+767.0769x=-78239.659646122323, y-0.812569429x=122.92554143245927, y-0.5354377x=-95.642334604813726.
Nebraska(id,x,y) :- id=21, y-0.812569429x=-122.92554143245927, y-0.6772147x=109.11268824821668, y+0.4046615x=3.0909835738065468.
Nebraska(id,x,y) :- id=22, y+0.5839300758x=-14.476979570345271, y+0.9629612x=-51.621275131781204, y+3.907157464x=-333.83514372187852.
Nebraska(id,x,y) :- id=23, y+0.717973005x=-26.980558205067581, y-0.07734876x=50.327023896365475, y+0.3323169x=10.180609684698609.
Nebraska(id,x,y) :- id=24, y-0.5354377x=-95.642334604813726, y+1.257943925x=-80.913392523370831, y-0.5624753424x=-98.401546175956653.
Nebraska(id,x,y) :- id=25, y+0.9981534162x=-60.861555013225789, x=-104.054300, y+0.9971552628x=-60.759692858212794.
Nebraska(id,x,y) :- id=26, y-0.5624753424x=-98.401546175956653, y+0.0007204222x=-42.925636975667778, y+0.9981534162x=-60.861555013225789.
Nebraska(id,x,y) :- id=27, y-0.7801837x=-119.20344488189201, y-0.2657269642x=68.787711041502888, y+0.07412223667x=-35.613365279581153.
Nebraska(id,x,y) :- id=28, y-0.2657269642x=68.787711041502888, y-0.1974417165x=62.095893336084188, y+0.06003937x=-36.98806289370448.
Nebraska(id,x,y) :- id=29, y+1.429118774x=-96.105989272013517, y+0.1012433392x=33.020211367669986, y+0.278974359x=-15.691383282051756.
Nebraska(id,x,y) :- id=30, y+3.089256198x=-255.47337553716935, y-1.413907285x=178.44380231789836, y+1.58985667x=-110.90307232635891.
Nebraska(id,x,y) :- id=31, y+0.6465061656x=-19.938675866119091, y+0.9272237x=-47.06601320753623, y+0.5683183x=-12.356307732735637.
Nebraska(id,x,y) :- id=32, y+3.089256198x=-255.47337553716937, y+0.6818811x=-23.35715269709678, y+1.206921413x=-74.094795602019175.
Nebraska(id,x,y) :- id=33, y+0.6339805825x=-18.981418058256267, y+1.488619x=-101.23200182094594, y+4.545139x=-394.98922638884267.
Nebraska(id,x,y) :- id=34, y+1.034648x=-57.494779092008159, y+1.431837426x=-95.767320237089379, y+2.398256x=-188.77561918600122.
Nebraska(id,x,y) :- id=35, y+1.431837426x=-95.767320237089365, y+2.173796x=-167.26116408477745, y+2.793494x=-226.8133861386076.

```

FIGURE 4.3: Snippet of the constraint database of the US map

As afore mentioned, the location of a sea turtle at a time is defined by its longitude and latitude. This means the location of the sea turtle changes as either (or both) the longitude and latitude change. Therefore, the constraint database is represented by the linear variation of the latitude in time and the linear variation of longitude in time. Because there is large quantity of data points, Java program is prepared to convert the large data into a constraint database of MLPQ system for each sea turtle. A snippet of the large MLPQ's constraint database for Irving is given in Figure 4.4.



```

US_irving - Notepad
File Edit Format View Help
irvingLonLat138830a(id,x,y,t) :- id=1,
x - 0.01287t >= -76.48180,
x - 0.01287t <= -76.23,
y - 0.00795t >= 34.43,
y - 0.00795t <= 34.68,
t >= 5.00, t <= 16.20.

irvingLonLat138830a(id,x,y,t) :- id=1,
x - 0.01395t >= -76.33760,
x - 0.01395t <= -76.09,
y - 0.00880t >= 34.51,
y - 0.00880t <= 34.76,
t >= 16.20, t <= 27.20.

irvingLonLat138830a(id,x,y,t) :- id=1,
x - 0.01231t >= -76.18420,
x - 0.01231t <= -75.93,
y - 0.00941t >= 34.61,
y - 0.00941t <= 34.86,
t >= 27.20, t <= 38.00.

irvingLonLat138830a(id,x,y,t) :- id=1,
x - 0.01211t >= -76.05120,
x - 0.01211t <= -75.80,
y - 0.00948t >= 34.71,
y - 0.00948t <= 34.96,
t >= 38.00, t <= 48.80.

irvingLonLat138830a(id,x,y,t) :- id=1,
x - 0.01671t >= -75.92040,
x - 0.01671t <= -75.67,
y - 0.00907t >= 34.82,
y - 0.00907t <= 35.07,
t >= 48.80, t <= 59.80.

```

FIGURE 4.4: Snippet of the moving object constraint database of the Irving

## 4.5 Result and Analysis

Once the constraint database for MLPQ system is prepared, running it in MLPQ is what ensues in order to visualize the movement of the sea turtles in the Atlantic ocean. There is the US map where each state is delineated using latitude and longitude. A sea turtle is represented by square box which is out of scale.

Figure 4.5 is the series screen shots of running Dexter's moving object and US' geographical databases on MLPQ system. The screen shots were taken at about 10 steps, in a fairly constant manner. That means the denser the boxes are the more time Dexter took there. The arrows also indicate the direction of motion of Dexter.

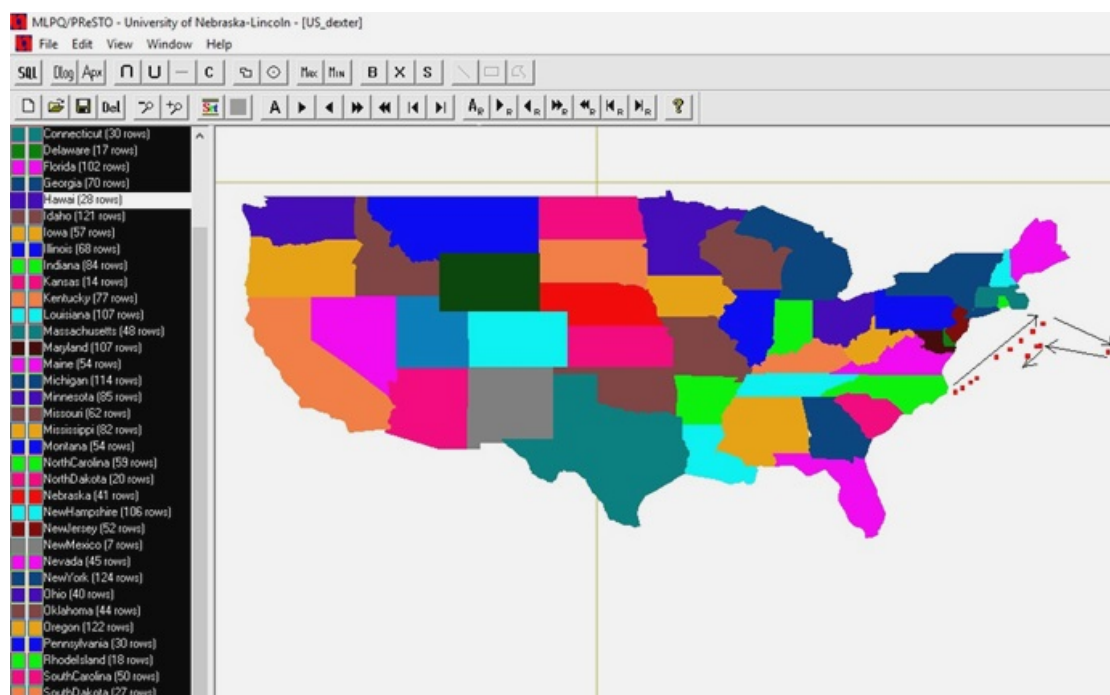


FIGURE 4.5: A series of screen shots of a running MLPQ system with US' geographical constraint database and Dexter's moving object constraint database.

Figure 4.6 also shows, like Figure 4.5, the series of screen shots of MLPQ system running the geographical and a moving object constraint databases for Irving. Each box represents the position of Irving in the Atlantic ocean in about 15 steps in the MLPQ

system. The density of the boxes represents the speed, inversely, and the arrows represent the direction of Irving. Finally, Figure 4.7 is like Figure 4.5 and Figure 4.6 with the sea turtle being Nala. The shots were taken at about 15 steps of MLPQ system. Since each step is fairly equal, the box density indicate how fast Nala was moving, while the direction is pointed by the arrows.

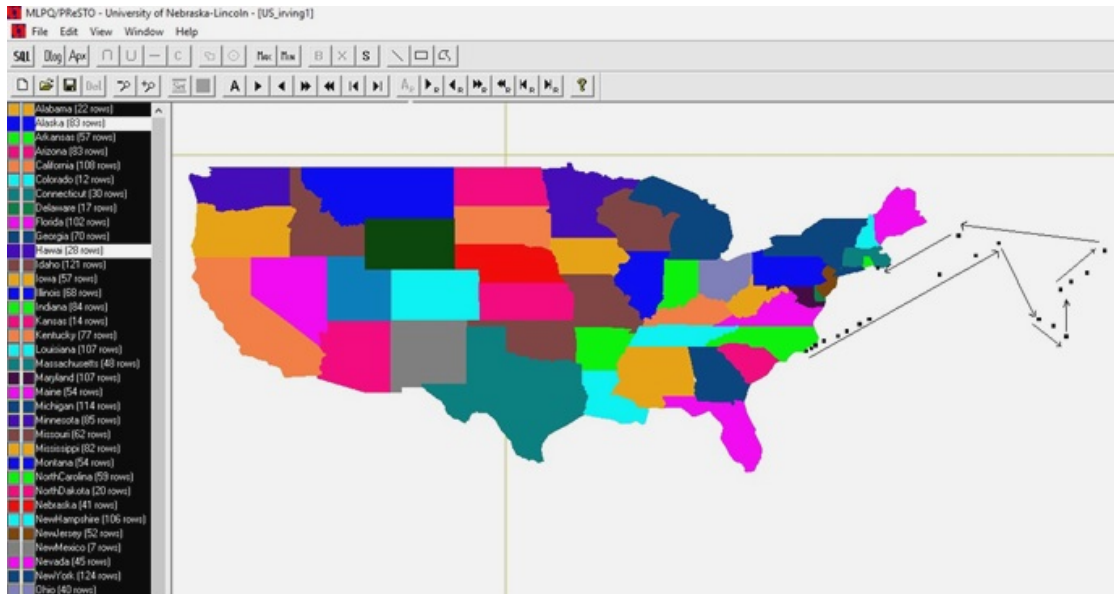


FIGURE 4.6: A series of screen shots of a running MLPQ system with US' geographical constraint database and Irving's moving object constraint database.



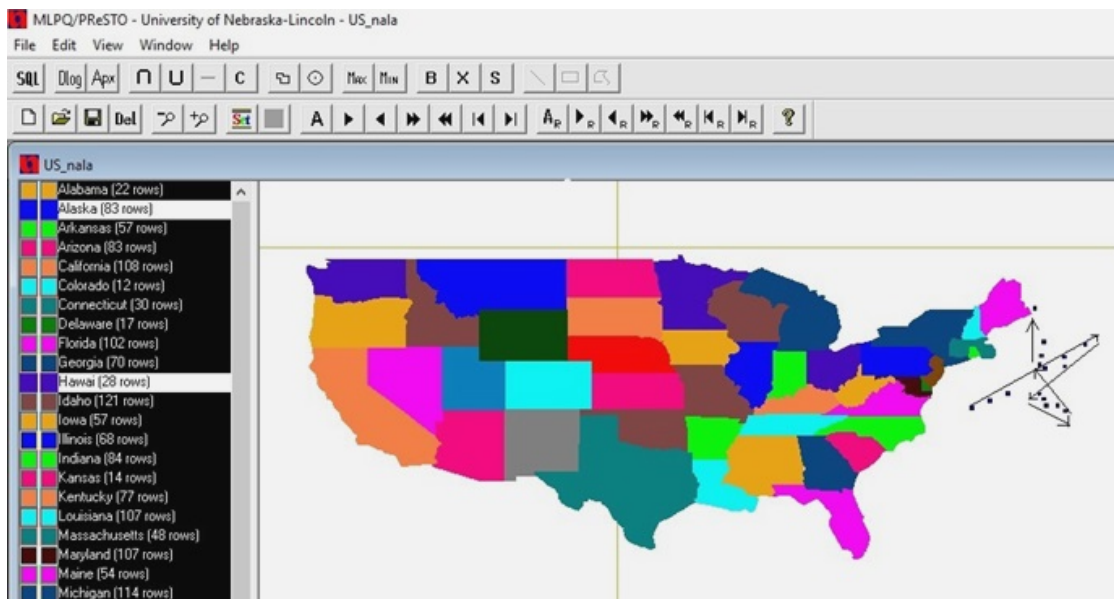


FIGURE 4.7: A series of screen shots of a running MLPQ system with US' geographical constraint database and Nala's moving object constraint database.

It is also important to check if it is possible to query the position of the turtles at a given time. For that purpose a query is made on Irving's location at time  $t = 150$  (the time is the number of hours since the start of recording). As shown in Figure 4.8, the position of irving (the top-right corner of the box representing irving), in the (longitude, latitude) form, is  $(-62.189499, 42.538502)$ .

**BASIC SQL**

VIEW NAME: Position(x,y)

SELECT: irvingLonLat138830a.x,irvingLonLat138830a.y

FROM: irvingLonLat138830a

WHERE: t=150

Buttons: OK, Cancel, Save, Load, Clear

(A) Query of irving's position at time  $t = 150$ 

**Property**

Position

x	y	CONSTRAINTS
x	y	<u><math>x \leq -62.189499</math></u> , <u><math>y \leq 42.538502</math></u> , $-x + 1.769111y <$

Buttons: Exit, Export

(B) The result query of irving's position at time  $t = 150$ 

FIGURE 4.8: The query and its result of irving's position at time  $t = 150$ . The underlined part indicates the position of the top-right corner of the box that represents irving.

Another important query that can be asked is (assuming the turtles are released into the ocean at the same time, which is not the case here in the data) “*Find the Easternmost turtle at time 250 hours.*” This type of query is something that does not have an easy way of answering in programming languages. Here, the answer to this question is completed in two simple extended SQL queries.

The first query is to get the positions of the sea turtles at the given time.

The screenshot shows a dialog box titled "BASIC SQL" with a close button (X) in the top right corner. It contains the following fields:

- VIEW NAME:** turtle250
- SELECT:** id, nx
- FROM:** turtle
- WHERE:** t = 250, nx + x = 0

At the bottom of the dialog box, there are five buttons: OK, Cancel, Save, Load, and Clear.

(A) Query of the position of all turtles at time  $t = 250$

The screenshot shows a dialog box titled "Property" with a close button (X) in the top right corner. It displays the results of the query in a table format. The table has three columns: id, nx, and CONSTRAINTS. The data is as follows:

id	nx	CONSTRAINTS
1	55.41	
3	66.35	

At the bottom of the dialog box, there are two buttons: Exit and Export.

(B) The result the query of the positions of all turtles at time  $t = 250$

FIGURE 4.9: The query and its result of the position of all turtles at time  $t = 250$ .

$x$  in the constraint database denotes the longitude of the turtles.  $nx$  and  $nx + x = 0$  are used to maintain positive values. The  $id$  denotes the identification number of the turtles on the database (1 = Irving, 2 = Dexter and 3 = Nala).

The next step query is to find the id of the turtle with the highest  $nx$  value in the table *turtle250*, as shown in Figure 4.10

NESTED SQL

VIEW NAME: Q2

SELECT: turtle250.id

FROM: turtle250

WHERE: turtle250.nx

<= all

SELECT: turtle250.nx

FROM: turtle250

WHERE:

OK Cancel Save Load Clear

(A) Query of the Easternmost turtle at time  $t = 250$

Property

Q2

turtle250_id	CONSTRAINTS
3	

Exit Export

(B) The result the query of the Eastern most turtle at time  $t = 250$

FIGURE 4.10: The query and its result of the position of all turtles at time  $t = 250$ .

The result is 3 which means *Nala* is the Easternmost with respect to the rest of the sea turtles.

## 4.6 Discussion and Conclusion

The data collection of the location of Dexter seems to start when the sea turtle was at the coast of North Carolina. After spending some time in the Atlantic ocean, it seems to head back to the North Carolina coast. Irving started from the coast of the North Carolina. It swam in a relatively wide area in the Atlantic ocean. The recording of its location ends when it gets near the coast of Rhode Island. *Nala* also was recorded near North Carolina coast and the recording ended near Maine. Dexter's migration shown by the MLPQ system seems to be consistent with the hypothesis that the sea turtles would return to their original place after migrating deep in the Atlantic ocean. Irvin and *Nala*, even though, they seem to return to a different US state, in the MLPQ system, it is important at this point to remember that the data used was trimmed at its beginning and its ending of the recording during the irregularity minimization process. So there is still a possibility that the turtles have returned to the same state. Moreover, in relation to the spread of the distance they travelled in the Atlantic ocean, the distance between the origin and the destination is not too far.

When running the geographical constraint database and the moving object database of the three sea turtles in the MLPQ system, there exist some random movements of the boxes which seem to be out of sync from what would be normally expected the box to move to. Moreover, at times, there exist double boxes for one turtle at one time. It is fair to assume that these drawbacks originate from the data itself rather than from the constraint database. The reason for that assumption is that, first, when a simulated data is converted into a moving object constraint database and is run in the system, there is no experience of abnormal movement. This is shown with simulation of a projectile motion and an inclined plane. The second reason is understood by analyzing the given

data of the location of the sea turtles. Looking at Figure 4.1, it can be seen that there are vertical lines on the graphs of the latitude and longitude. Vertical lines on these graphs mean that the sea turtles are existing at different latitude or longitude at the same time. To minimize such data aberration, averaging of neighbor data points was done. Even though, this method helps minimize such data aberration, it can't be expected to solve the problem completely.

Finally, query of the position of irving at time  $t = 150$  was made. The result of the query,  $(-62.189499, 42.538502)$ , is with in the Atlantic ocean, somewhere near the US coast(around Maine), which gives more confidence on the accuracy of the constraint database.

## Chapter 5

# Conclusion

A projectile motion constraint database was constructed using existing mathematical relations, as in Equations 2.5 and 2.6, on MLPQ system. In the constraint database, the trajectory of projectiles launched at  $30^\circ$ ,  $45^\circ$  and  $60^\circ$  were represented. In investigating the results obtained by constraint database, the projectiles' relative total time of flight, range and maximum height were in agreement with the theoretical expectation. Moreover, in order to test the absolute accuracy of the database, not relative to each other, the position of the projectile at random time was queried and the result was compared with its theoretical counterpart. A constraint database representing the motion of an object on an inclined plane, tilted at  $30^\circ$  and frictionless, was also constructed, using Equations 3.2 and 3.3, in MLPQ system. The accuracy of the database is substantiated by looking the total time the object on the inclined plane took to slide all the way on the inclined plane and by querying the its position at a random time. Both were compared with what would be expected theoretically. Both the projectile motion and the inclined plane problem are accelerated motions, and both were represented in a constraint database in this thesis.

Data obtained from a research that investigates the homing behavior of sea turtles (courtesy of Dr. Lohmann [7]), was also used to convert it into constraint database, in MLPQ system. The finite data, that represents the position, in latitude and longitude, of the sea turtles at certain date, was converted into constraint database. Converting a

finite data into constraint database in MLPQ system can provide a continuous motion animation in MLPQ system. Continuous motion animation gives a better perspective in viewing the migration of the sea turtles, instead of dotted data points on a map, and hence help make better analysis of the research results. The position data of the sea turtles, which is in the Atlantic ocean, is better understood with the map of the United States as reference. For this purpose, the latitude and longitude of the boundaries of all the states was used to create a geographical constraint database of the US map. A query on the position of one of the sea turtles was also done to show that an information can be queried from the constraint database.

Finally, on this thesis it was shown that some accelerated motion and complicated migration movement of sea turtles could be represented on a constraint database, which thereby can be queried and visualized. This may give an insight for a more generic approach to representing accelerated motion in constraint database.



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