

CREATING A HABITAT SUITABILITY INDEX TO PLAN FOR FUTURE SEAGRASS RESTORATION

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Seagrass Ecosystem Services

- ▣ Sediment stabilization
- ▣ Water filtration
- ▣ Protection from storms
- ▣ Habitat and nursery for commercial and recreational fish species

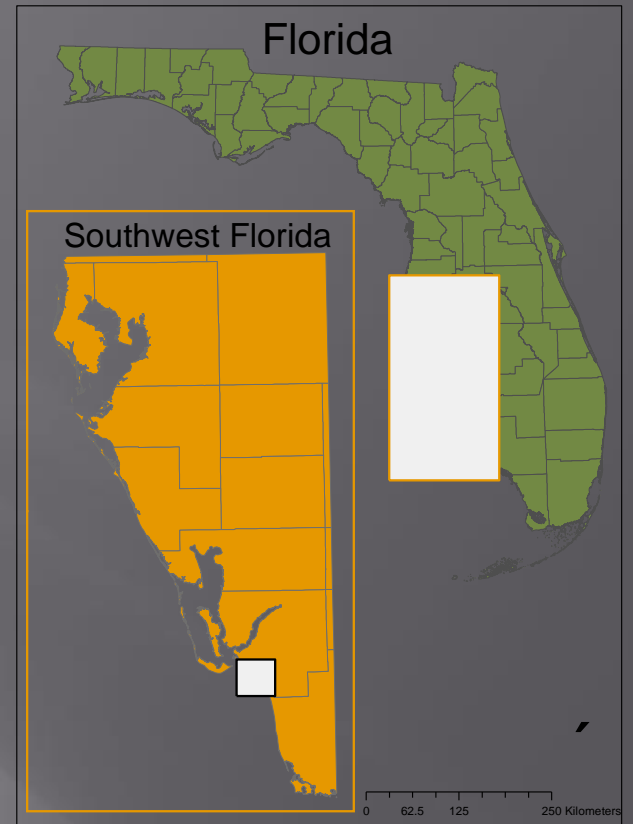
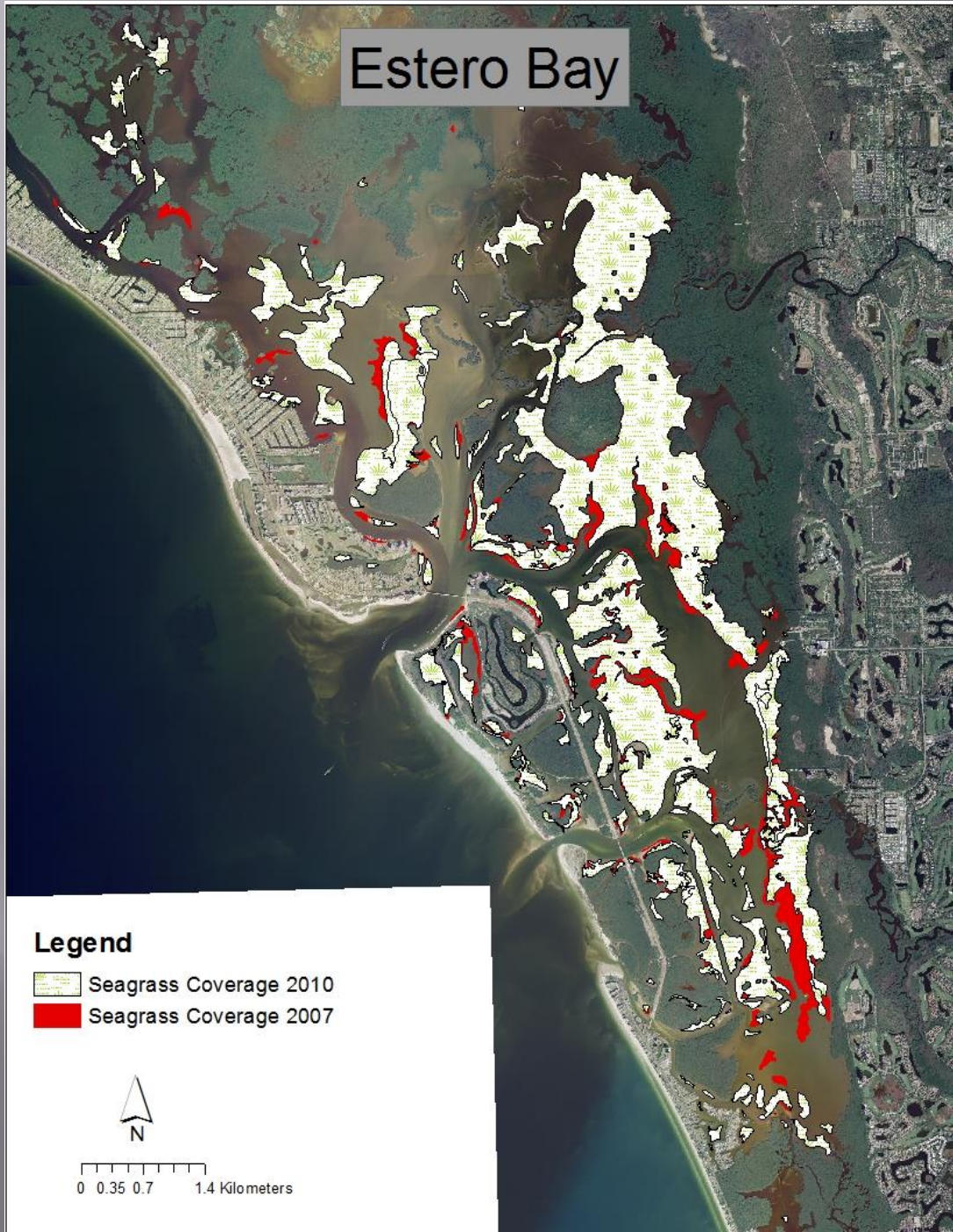


Loss

- ▣ In the last two decades the documented loss of seagrass has been 3.3 million hectares or 20% of total documented coverage in the world
- ▣ Estimated 1,600 hectares needs to be restored SW Florida



Estero Bay



Causes

- ▣ Direct loss of seagrass
 - Docks
 - Marinas
 - Navigation channels
 - Increase in boating (particularly by inexperienced boaters)
- ▣ Indirect causes of loss
 - Eutrophication
 - Sedimentation
 - Changing salt/freshwater flow patterns
 - Climate change
 - Sea level rise



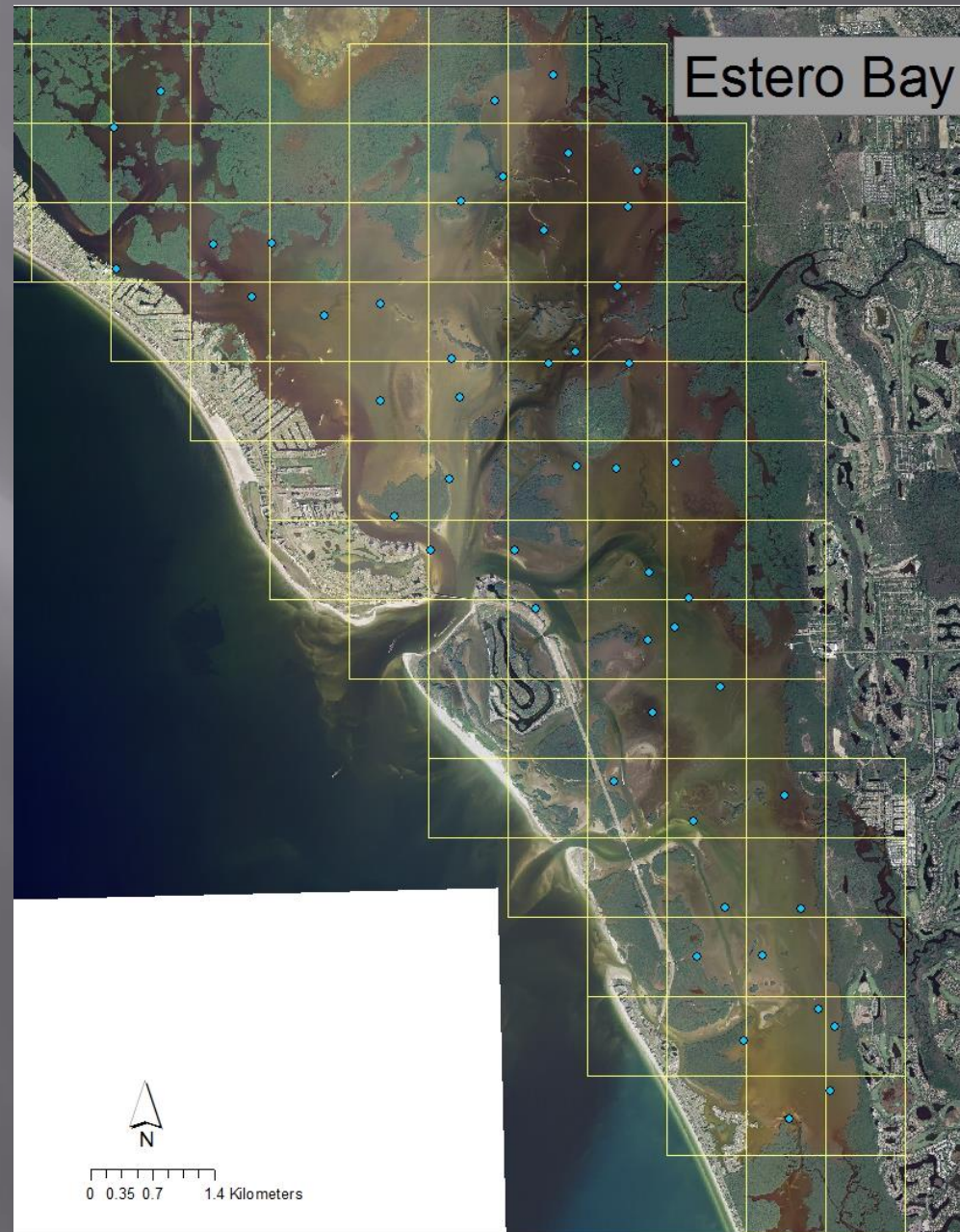
Habitat Suitability Index

- ▣ Identify areas of the bay that have a suitable light environment for seagrass restoration
 - Throughout Bay (Space)
 - Seasonality (Time)
- ▣ Improve science behind restoration site selection



Methods

- ▣ Stratified random sampling was used to identify 50 points in the bay
- ▣ Data collection occurred over 2 days every 3 weeks for a year
- ▣ Data recorded at each site
 - PAR (photosynthetically active radiation)
 - Water Depth
 - Salinity
 - Water Temperature
 - Dissolved Oxygen
 - Sampling Time



- ▣ PAR readings are paired, one on the surface and one 25 cm from the bottom
 - Between 10 am and 2 pm
 - 3 replicate measurements are made more than 30 sec apart at each site
- ▣ The percent of light available at the bottom is calculated for each reading and then the 3 percentages obtained for that sampling event are averaged
- ▣ LI-COR LI-1400 Data Logger
- ▣ Paired LI-COR LI-193SA Underwater Spherical Quantum Sensors



Light attenuation coefficients (K_d)

- ▣ Calculated from paired light readings using the Lambert-Beer Law:

$$I_z = I_0 e^{-(K_d)z}$$

- ▣ Where I_z is light measured at depth z , I_0 is light measured at the surface and K_d is the light attenuation coefficient in units of m^{-1}
- ▣ For each of the 50 sites the average K_d , minimum K_d , max K_d , lower quartile, upper quartile, and 90th percentile was calculated.

Kriging

- ▣ Geostatistics- uses statistical theory and software to analyze data with location coordinates
- ▣ Kriging allows you to predict values where no measurements have been taken
 - Measure the error of your prediction
- ▣ ArcGIS 10.1, Geostatistical Analyst
- ▣ Ordinary, simple, and universal kriging models were fit to the data
- ▣ Transformations, trend removals, anisotropy, and an iterative cross validation techniques was used to optimize model parameters
- ▣ Model with the smallest root mean square error was selected in each case

A

Value 10

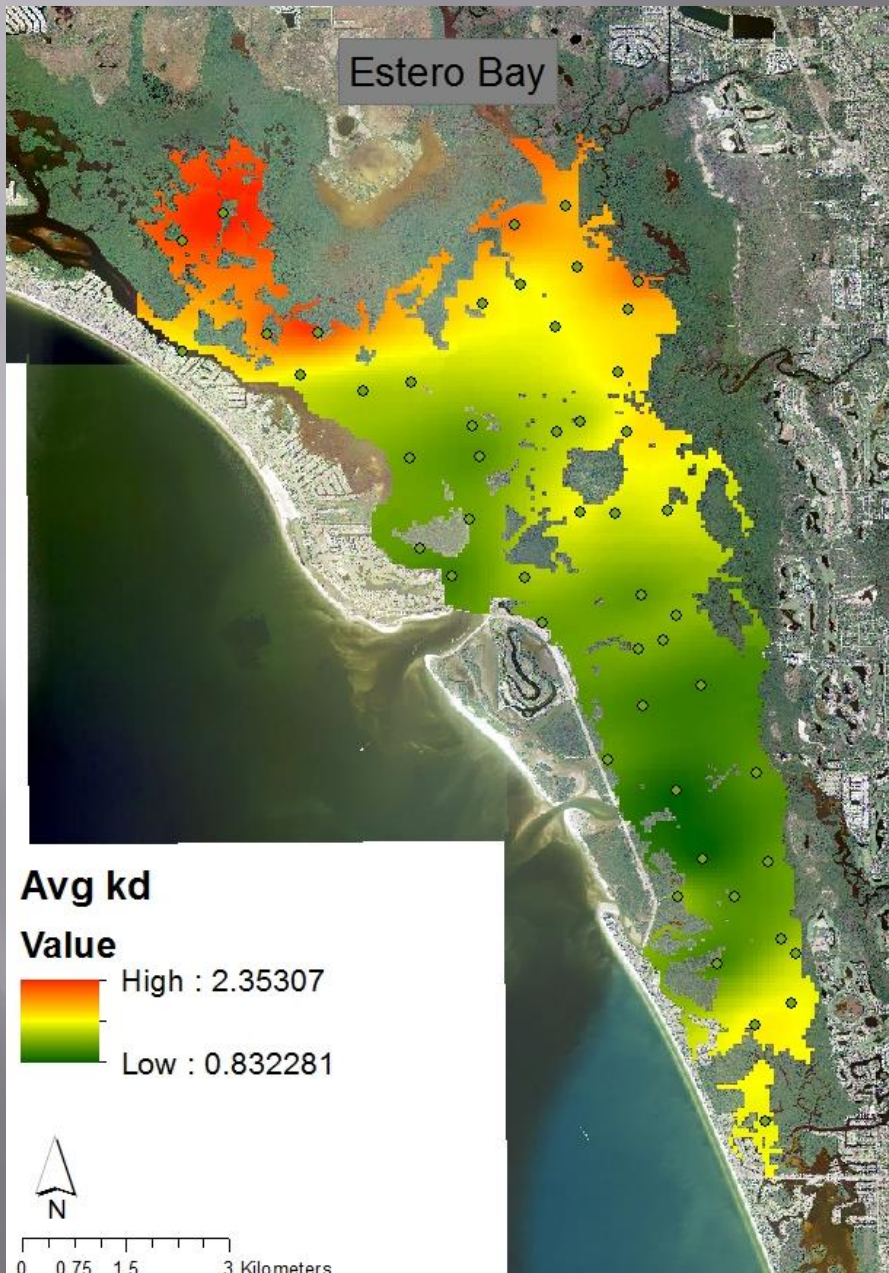
B

Value ?

C

Value 20

Water Clarity



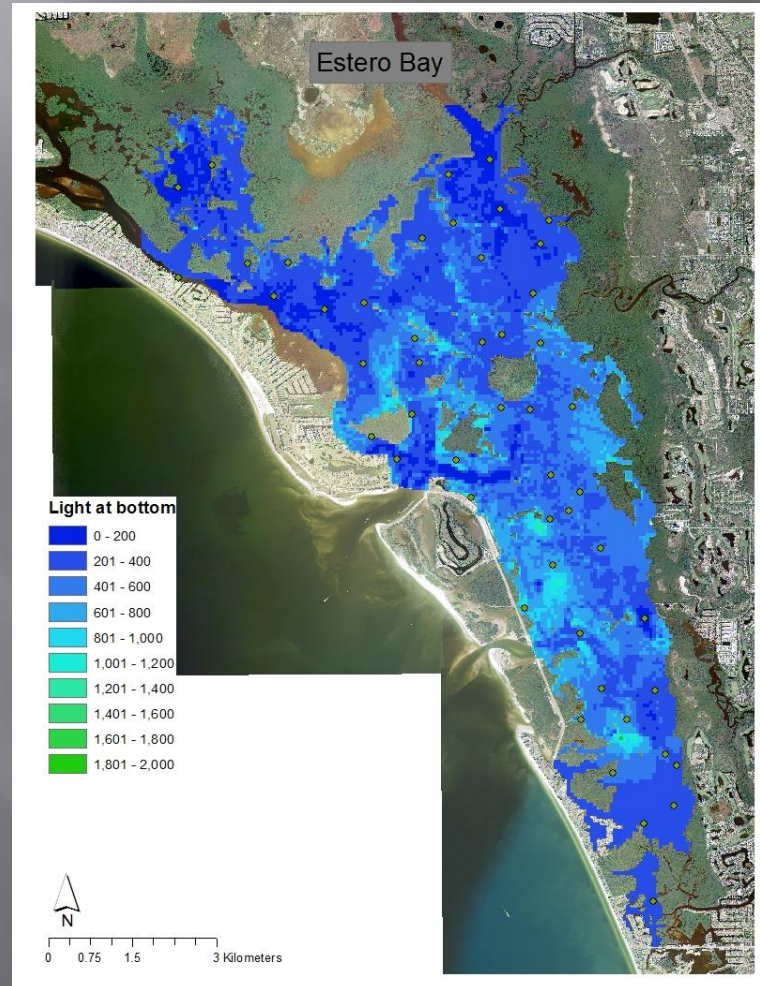
- ❑ Convert to raster
- ❑ Spatial Analyst Tools
 - Map Algebra
 - Raster Calculator
- ❑ Use depths from dense Lidar bathymetry layer
- ❑ Using Lambert Beers Law with known depths and predicted kd can predict light available at the bottom under average surface light conditions

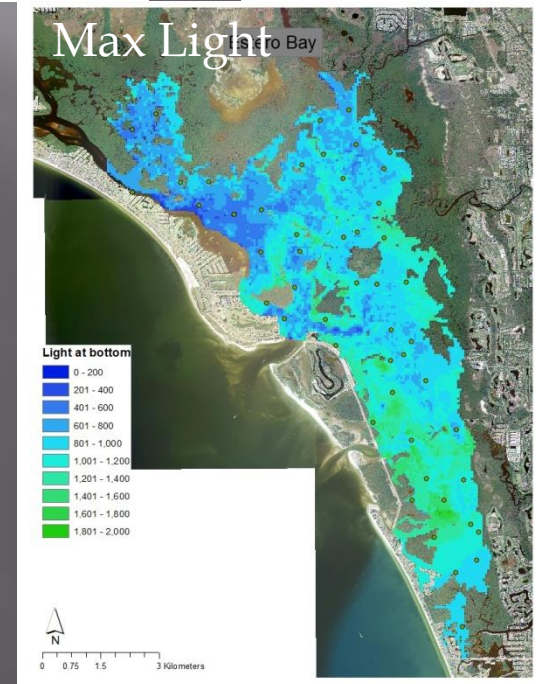
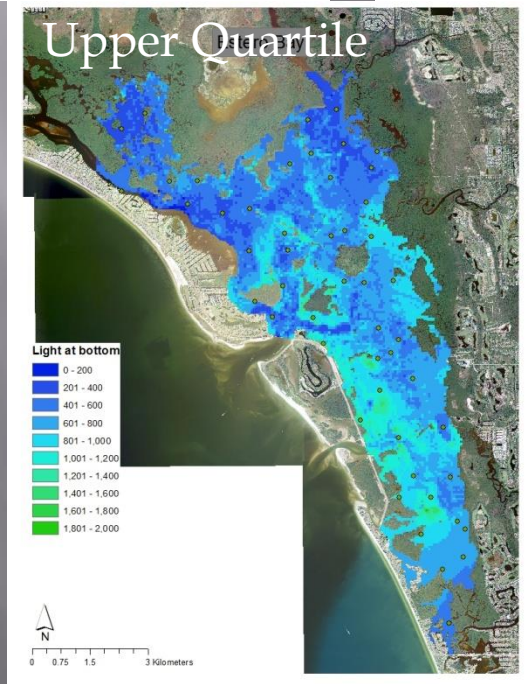
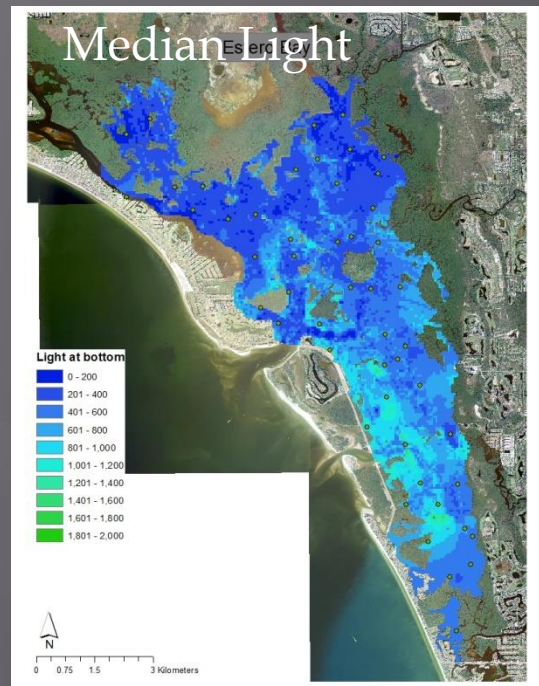
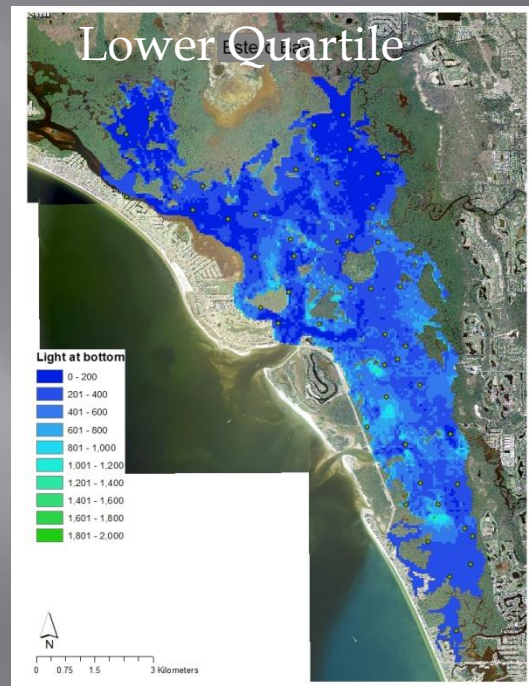
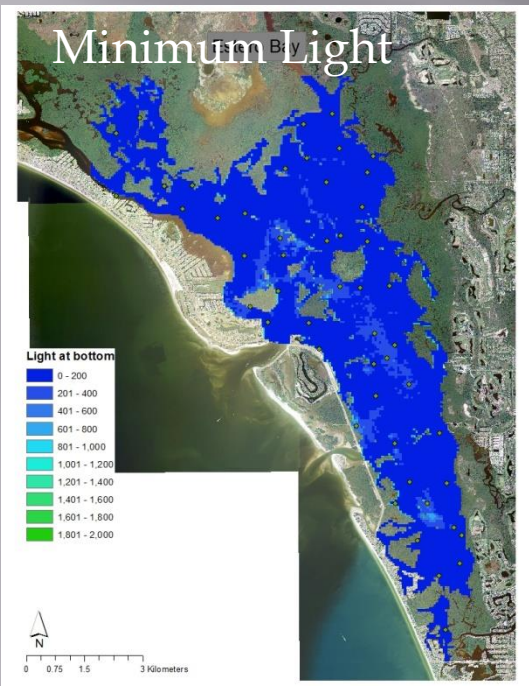
Bathymetry

- ▣ 816,218 depths
- ▣ Lidar
- ▣ Collected by USGS for South Florida Water Management District
- ▣ 2003
- ▣ NASA EAARL lidar

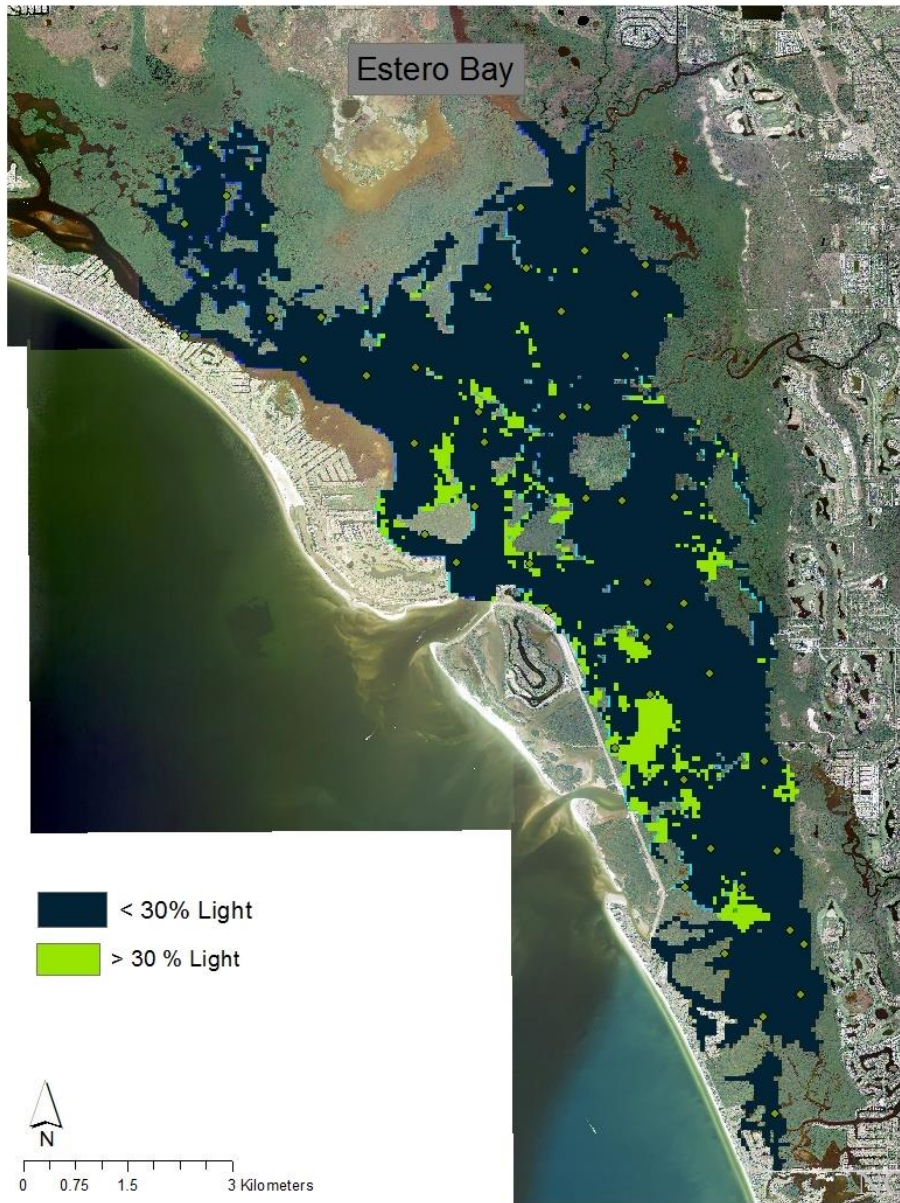


Average Amount of Light (μmol photons) Available at the Bottom of Estero Bay

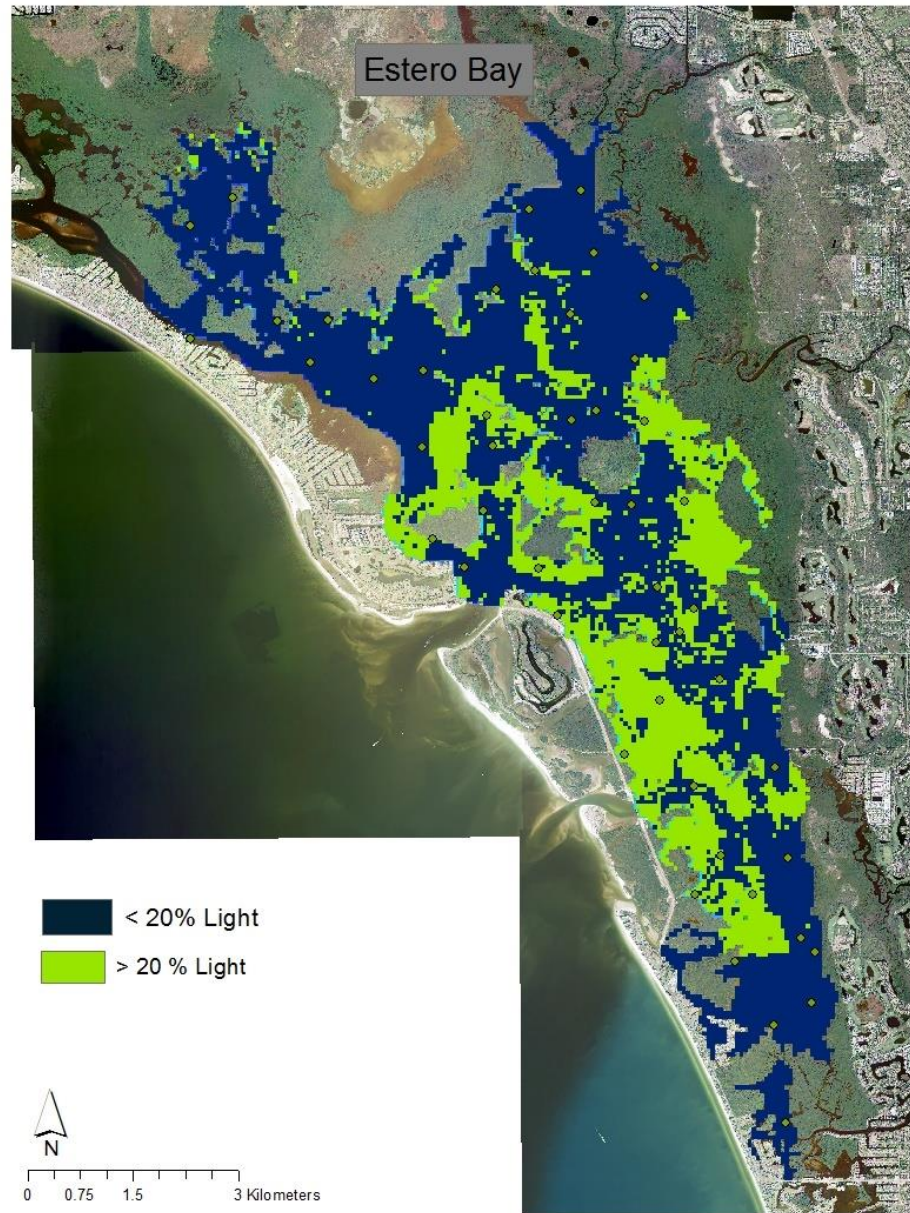




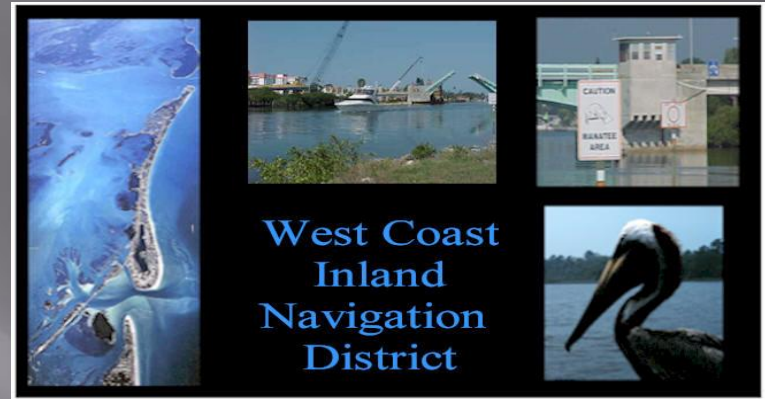
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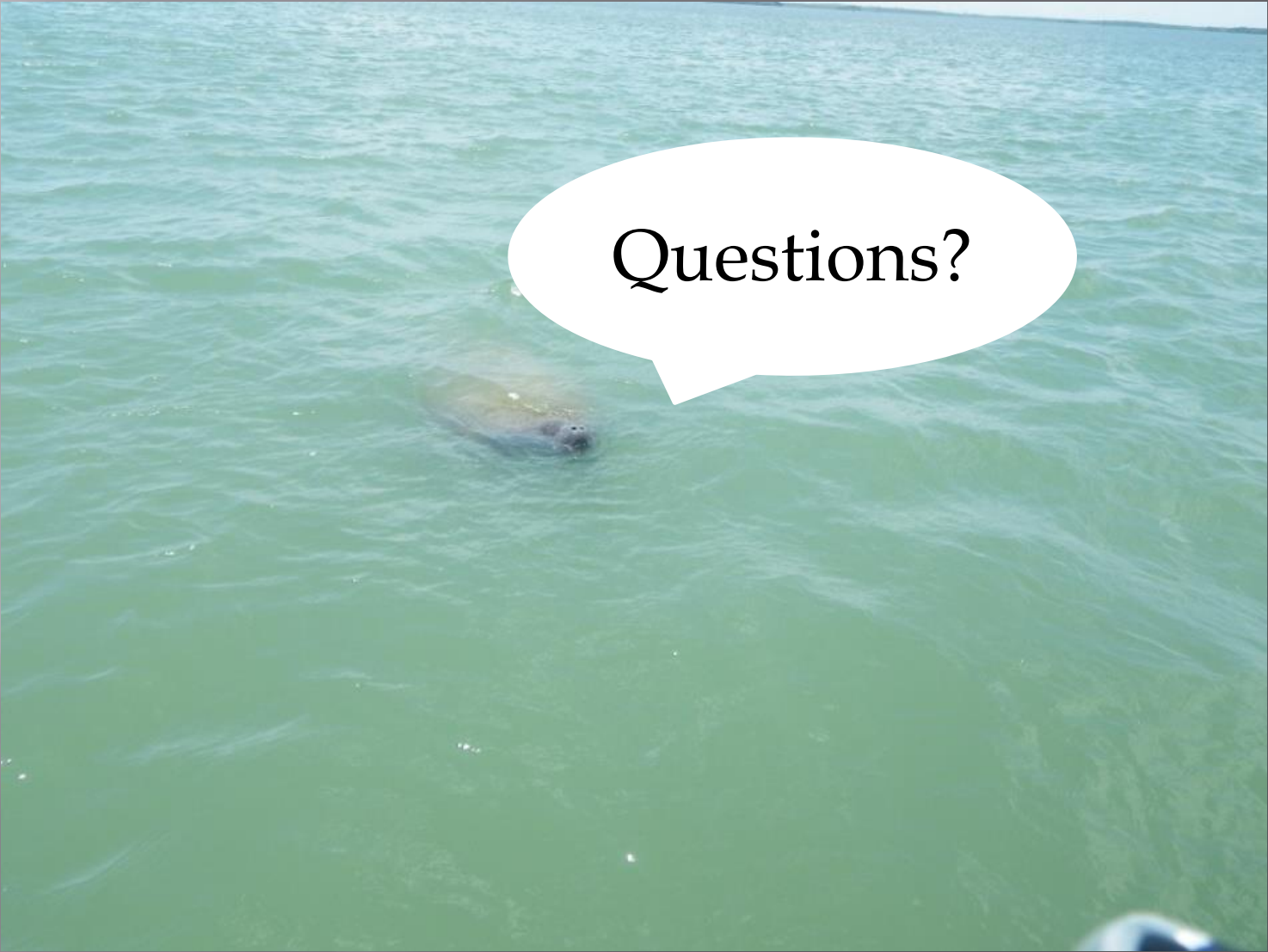


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Acknowledgements





Questions?