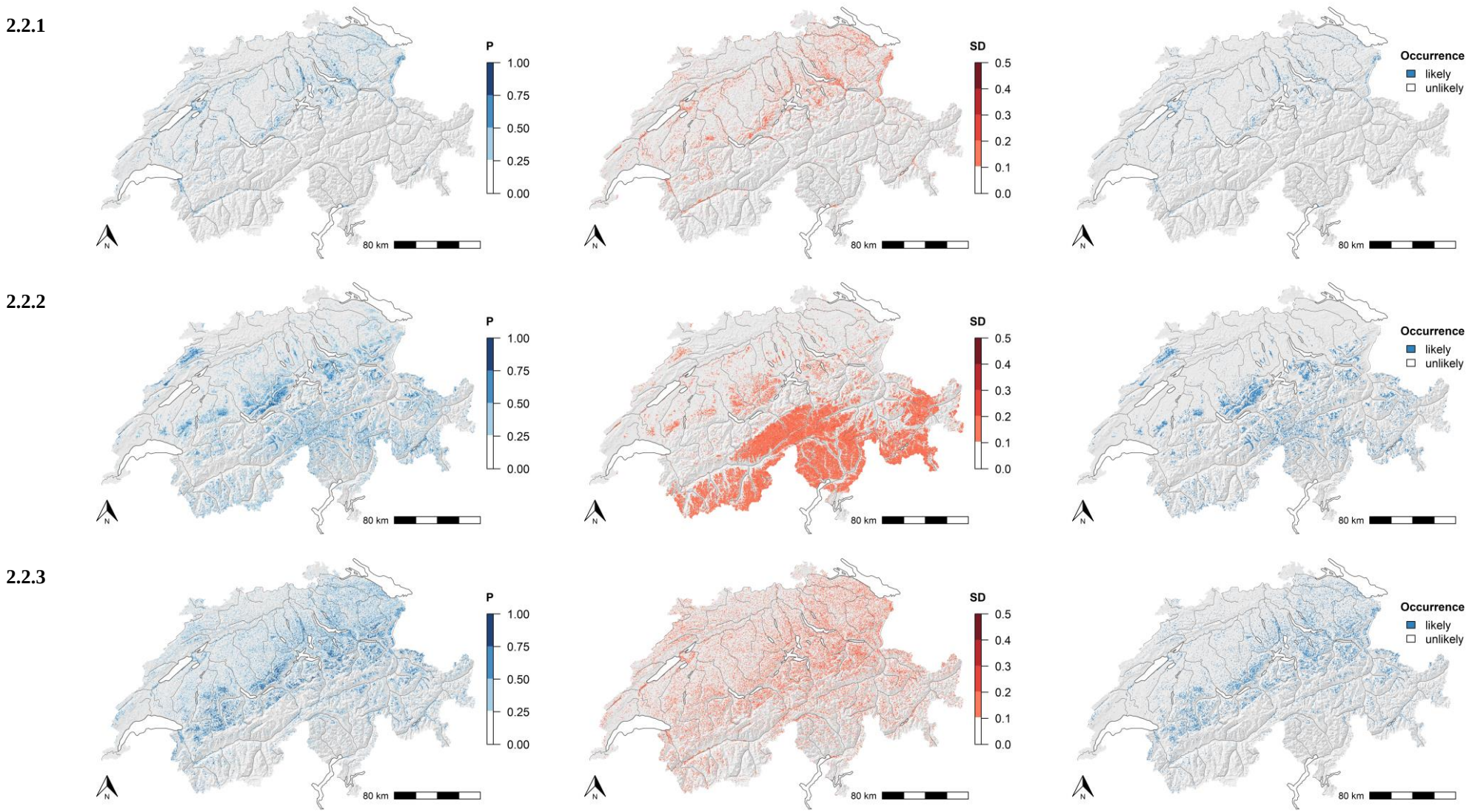


Fig. 1: Countrywide ensemble maps (4 model types, 10 CV runs) of the individual habitat types (TypoCH). For the presence/absence maps, the predicted probabilities of occurrence were first transformed to individual presence/absence maps for each model type and CV run based on the threshold maximizing TSS. Then, these maps were aggregated by assigning a potential presence ('Occurrence likely') if more than half of the individual maps reported a presence for the respective pixel, otherwise an absence ('Occurrence unlikely') was assigned.

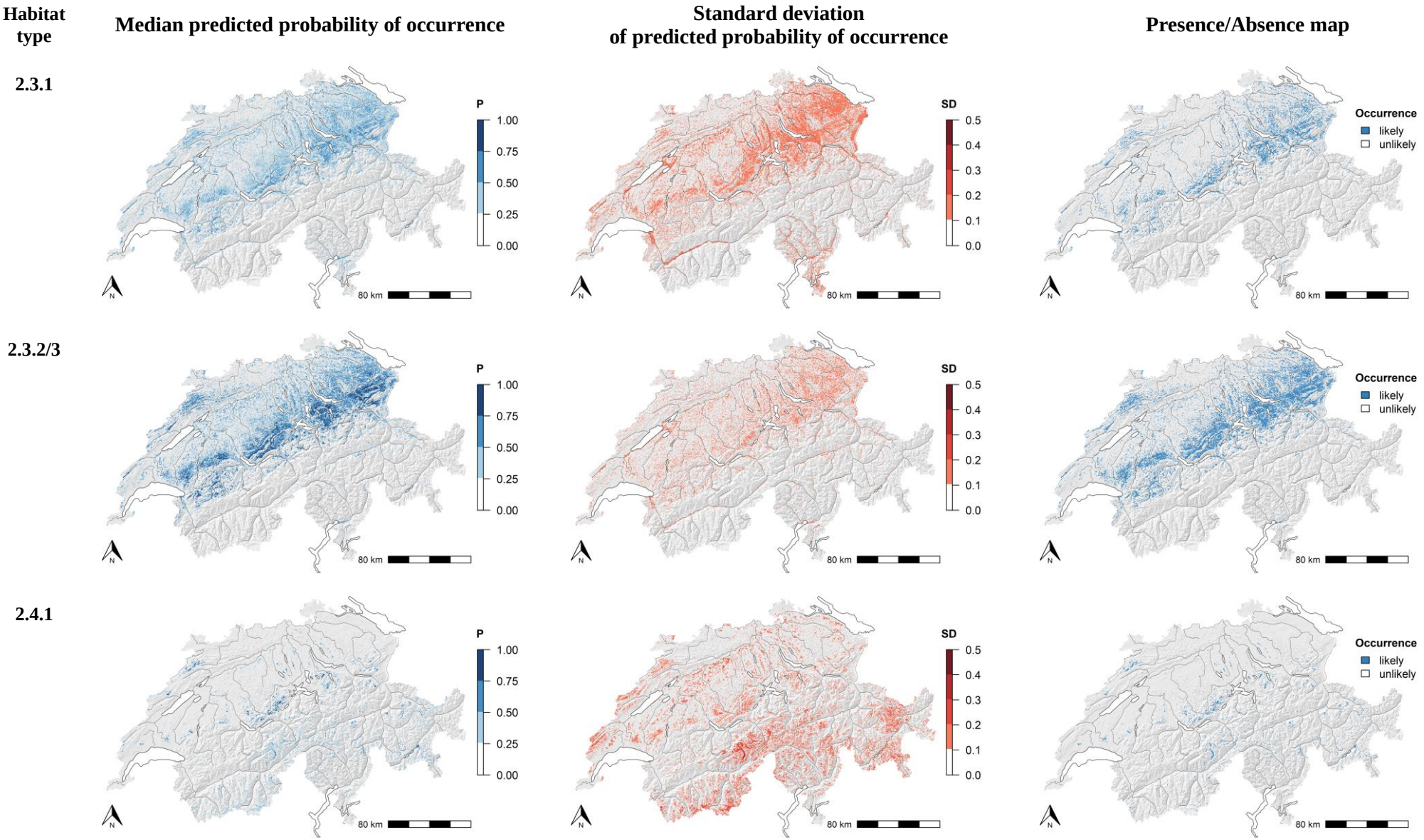


Fig. 1 continued: Countrywide ensemble maps (4 model types, 10 CV runs) of the individual habitat types (TypoCH). For the presence/absence maps, the predicted probabilities of occurrence were first transformed to individual presence/absence maps for each model type and CV run based on the threshold maximizing TSS. Then, these maps were aggregated by assigning a potential presence ('Occurrence likely') if more than half of the individual maps reported a presence for the respective pixel, otherwise an absence ('Occurrence unlikely') was assigned.

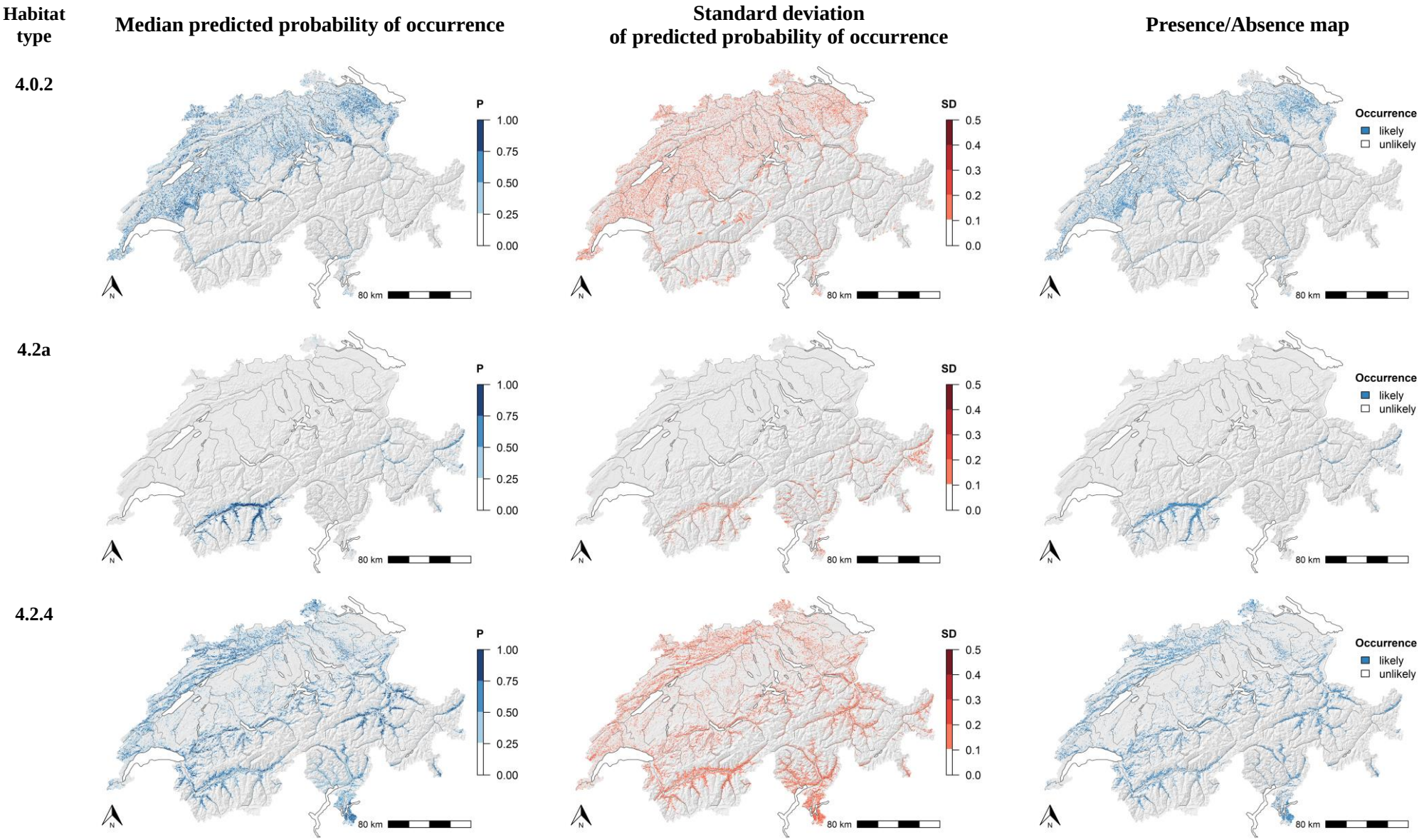
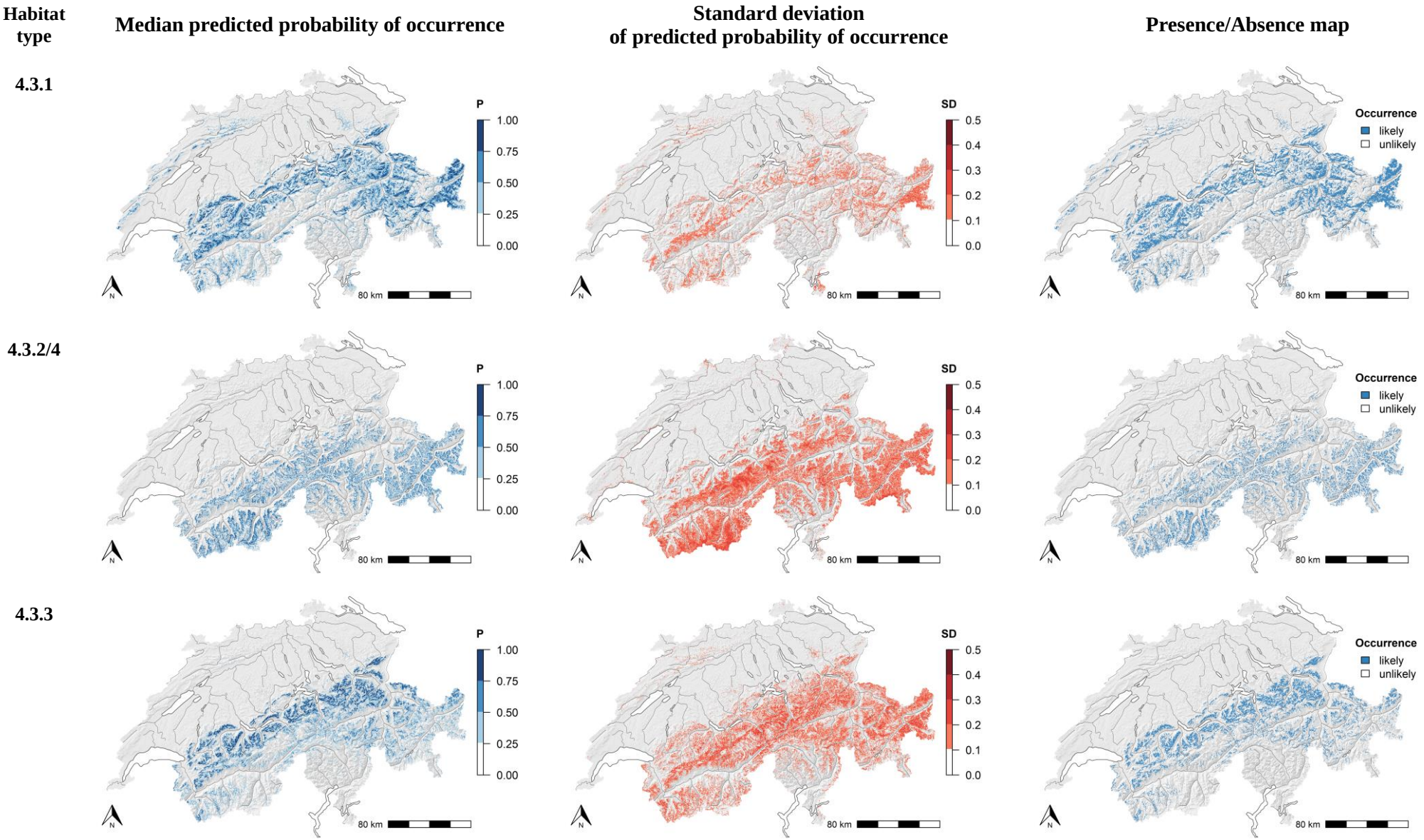


Fig. 1 continued: Countrywide ensemble maps (4 model types, 10 CV runs) of the individual habitat types (TypoCH). For the presence/absence maps, the predicted probabilities of occurrence were first transformed to individual presence/absence maps for each model type and CV run based on the threshold maximizing TSS. Then, these maps were aggregated by assigning a potential presence ('Occurrence likely') if more than half of the individual maps reported a presence for the respective pixel, otherwise an absence ('Occurrence unlikely') was assigned.



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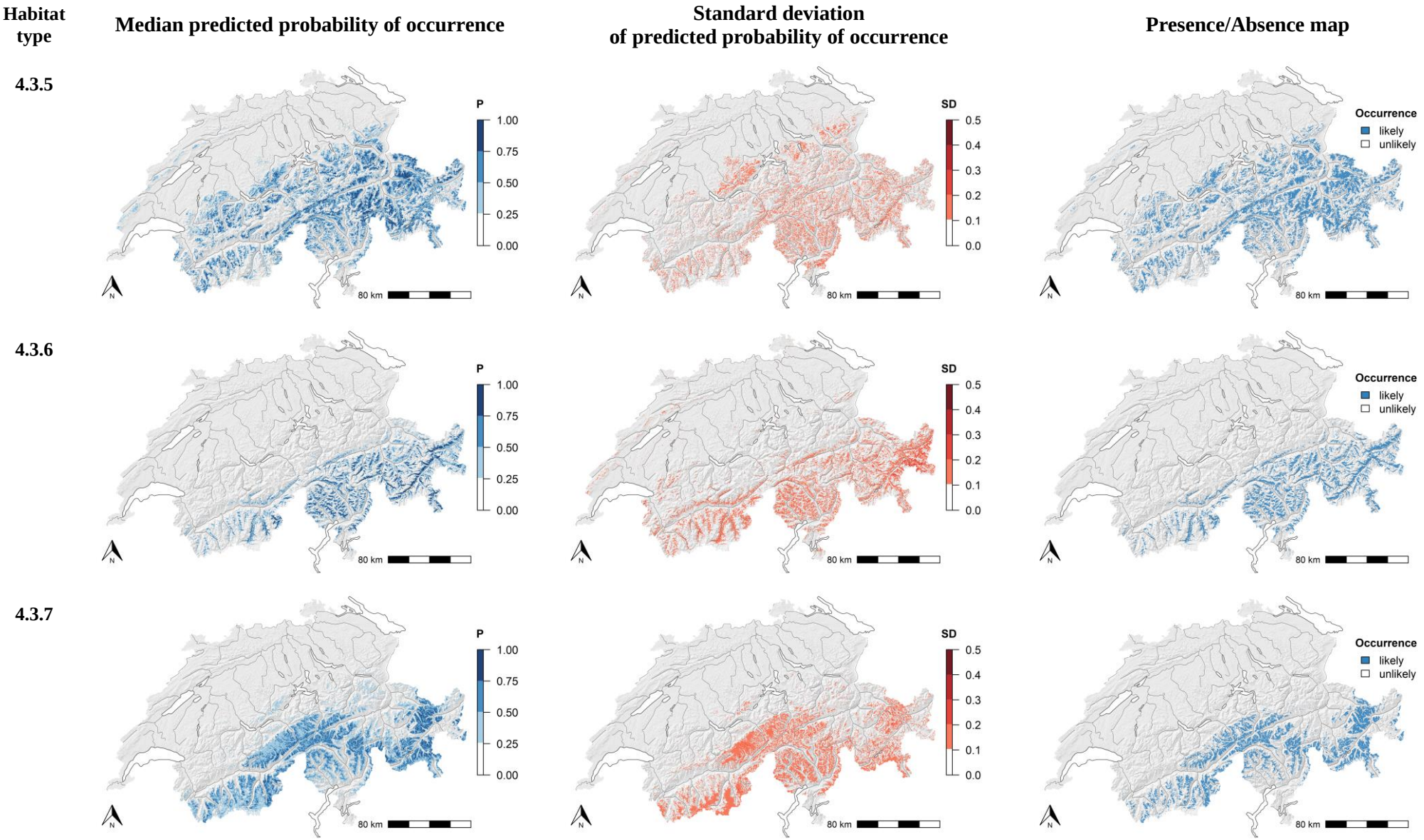

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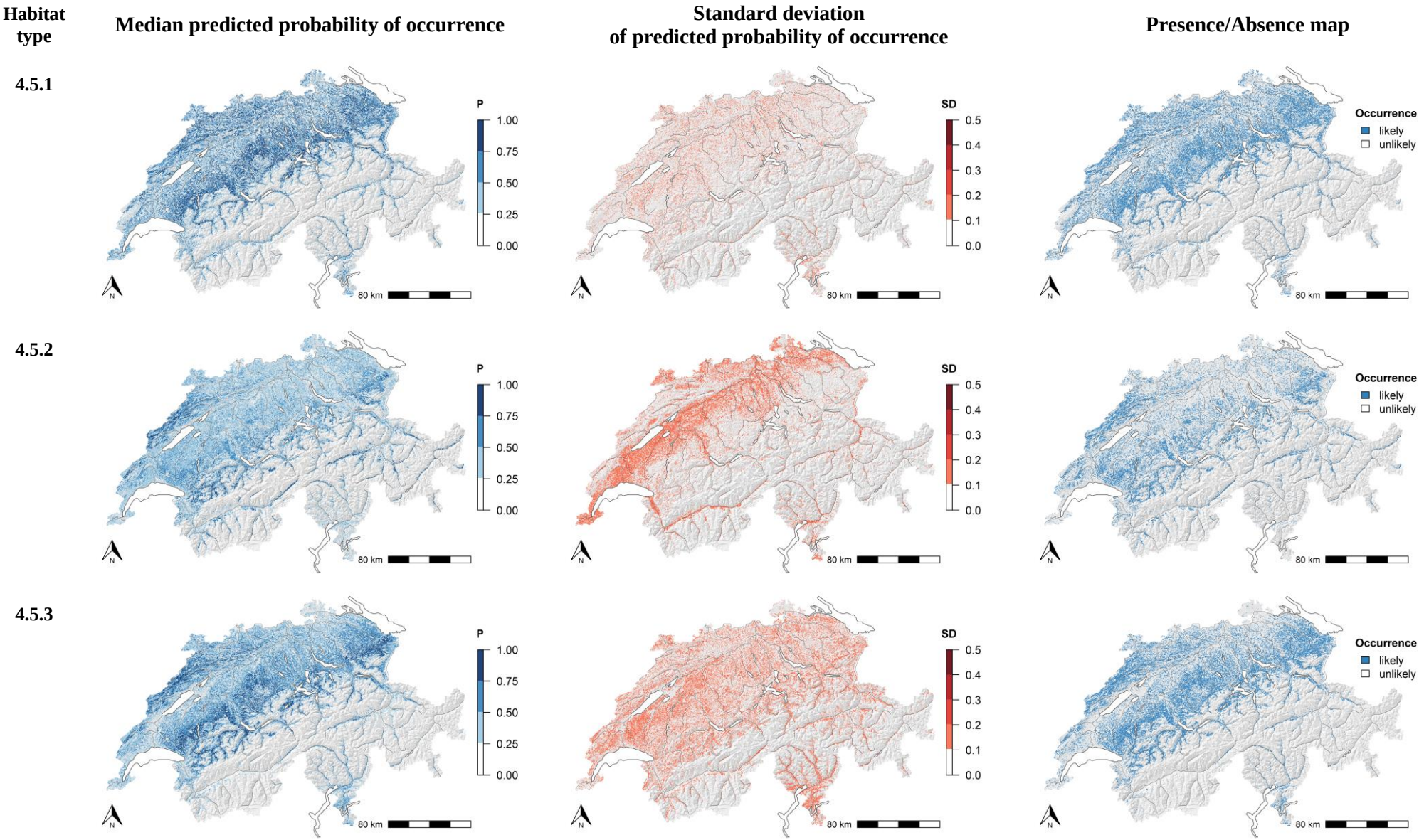
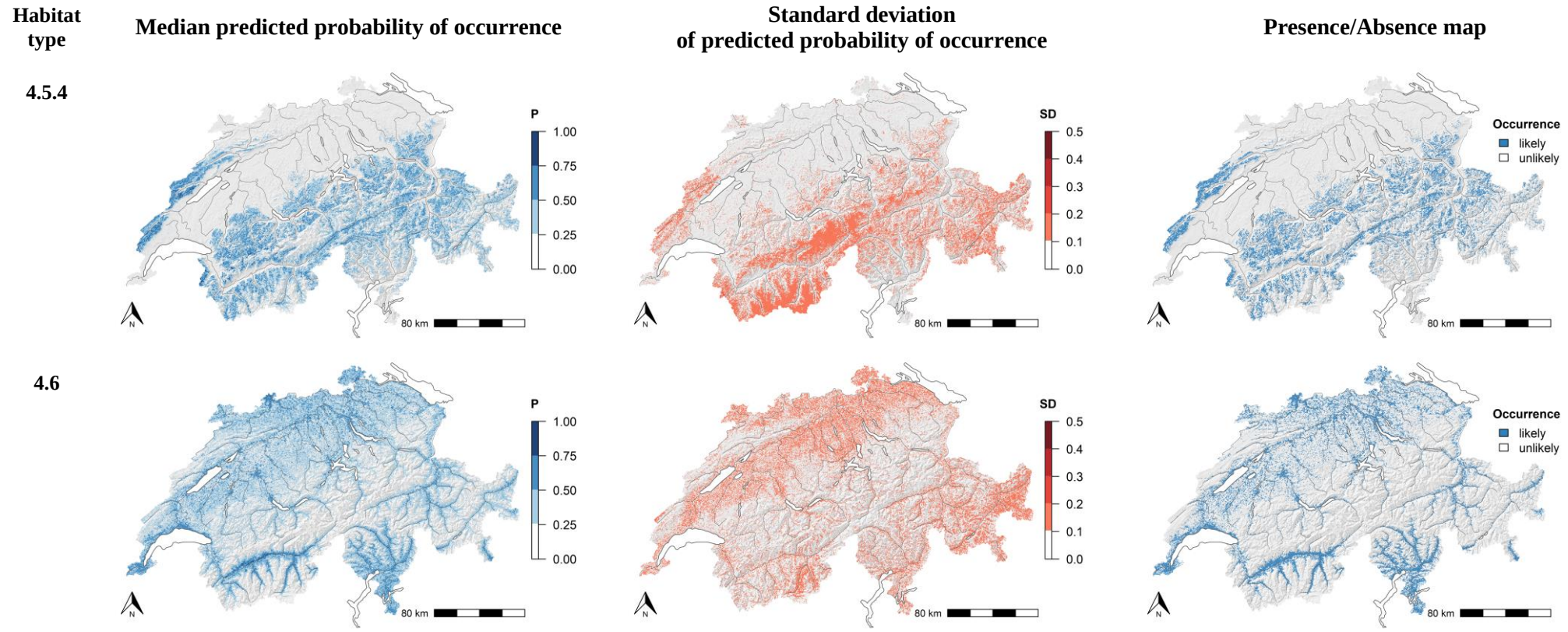


Fig. 1 continued: Countrywide ensemble maps (4 model types, 10 CV runs) of the individual habitat types (TypoCH). For the presence/absence maps, the predicted probabilities of occurrence were first transformed to individual presence/absence maps for each model type and CV run based on the threshold maximizing TSS. Then, these maps were aggregated by assigning a potential presence ('Occurrence likely') if more than half of the individual maps reported a presence for the respective pixel, otherwise an absence ('Occurrence unlikely') was assigned.



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