

Appendix

Geodata-Guided Defrosting Robot:
Image Segmentation for Path Planning

Submission date: 03/06/2024

Course code: KISPECI1SE

Programme: Msc. Software Design

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1. Tile2Net Segmentation Results

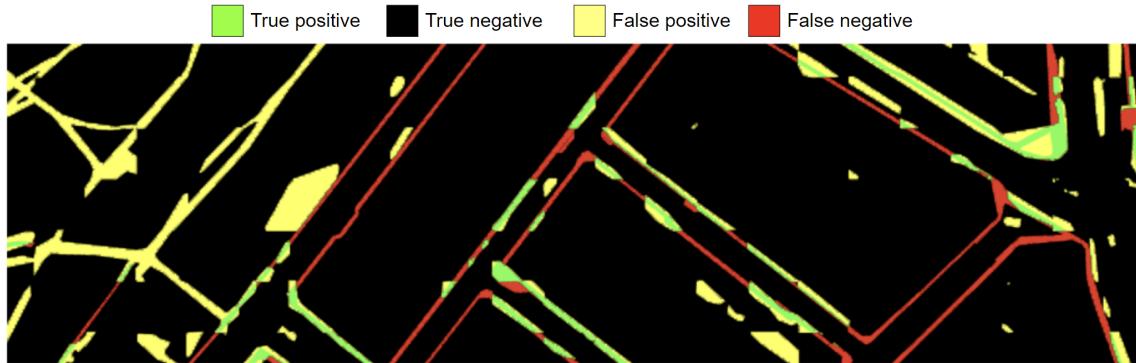


Figure 1.1: Tile2Net - Location 1.

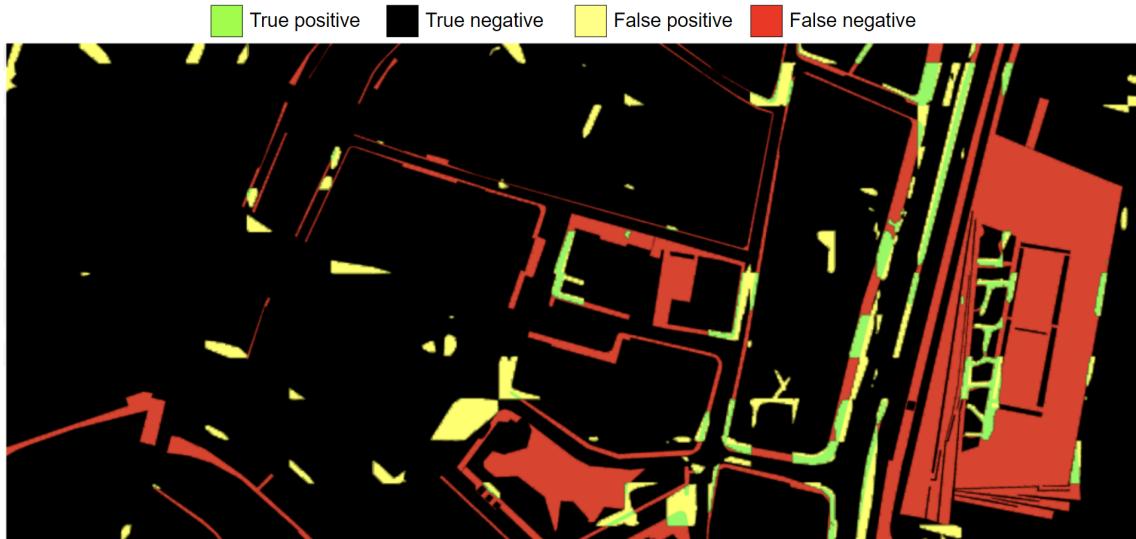


Figure 1.2: Tile2Net - Location 2.

True positive True negative False positive False negative

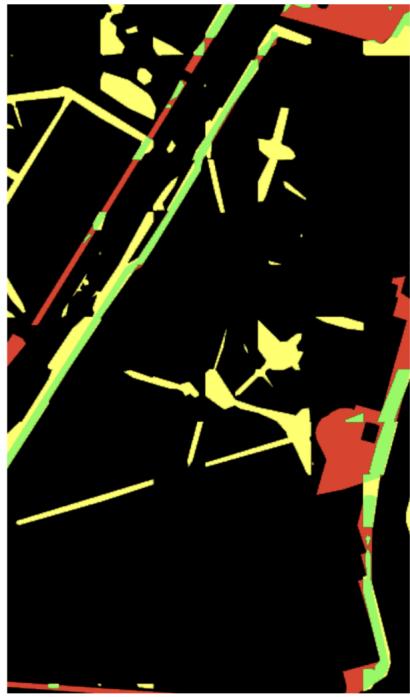


Figure 1.3: Tile2Net - Location 3.

True positive True negative False positive False negative

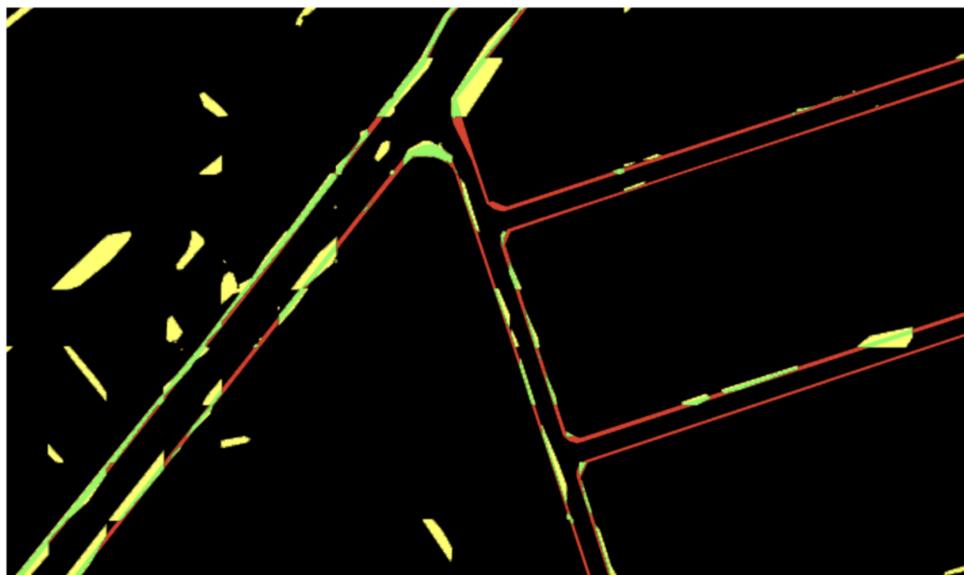


Figure 1.4: Tile2Net - Location 4.

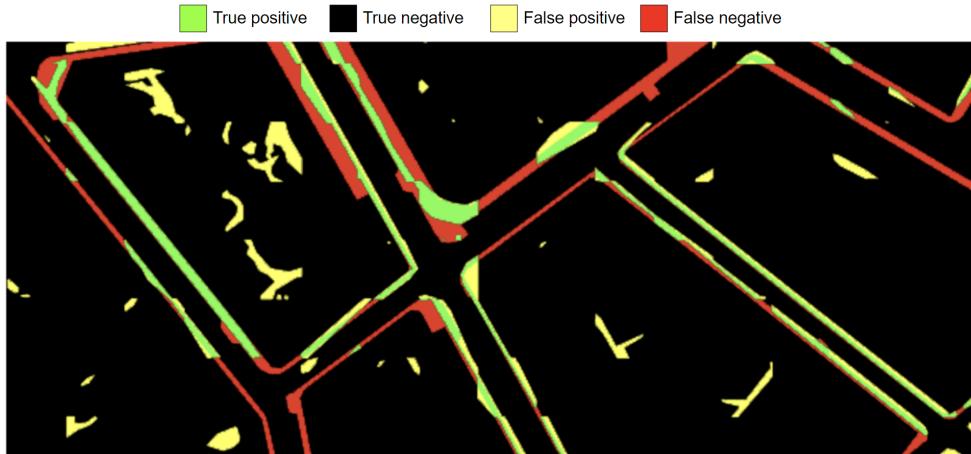


Figure 1.5: Tile2Net - Location 5.

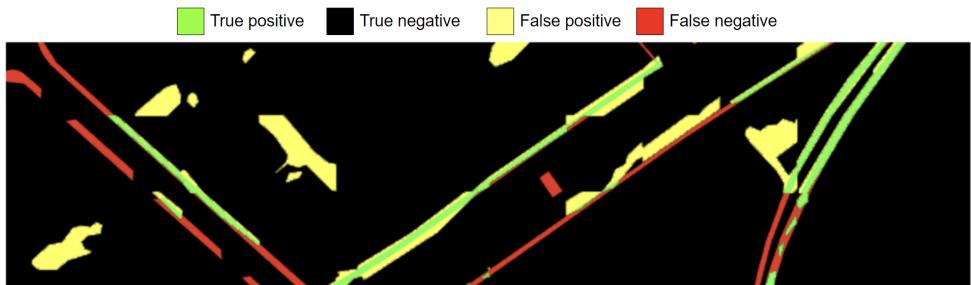


Figure 1.6: Tile2Net - Location 6.

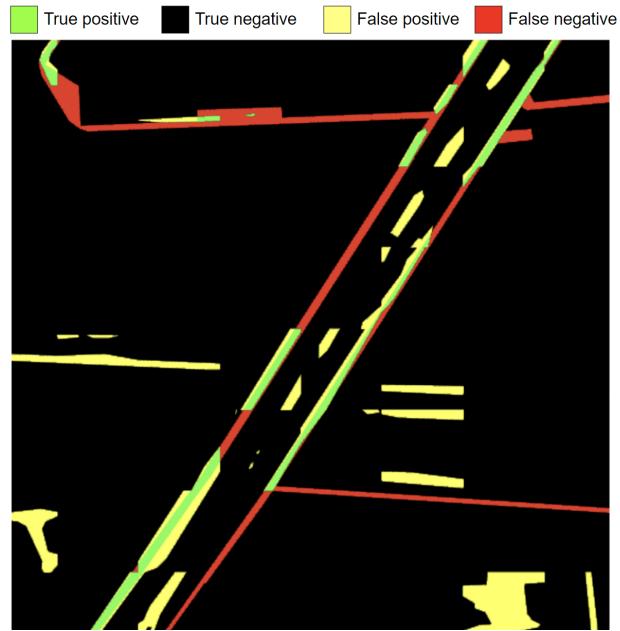


Figure 1.7: Tile2Net - Location 7.

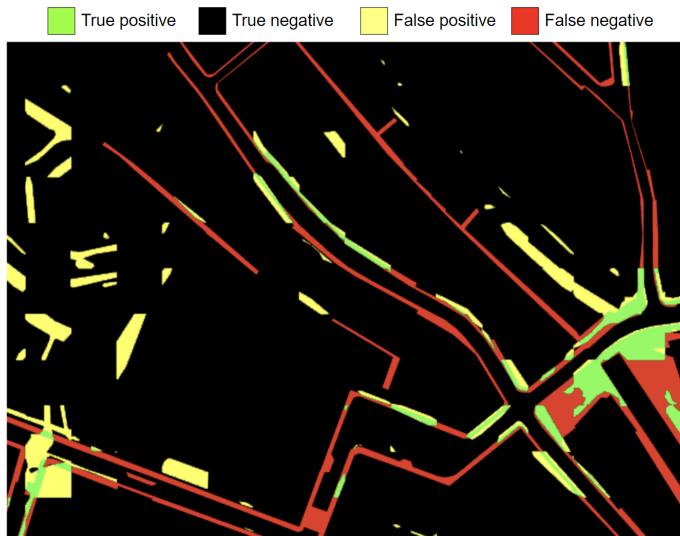


Figure 1.8: Tile2Net - Location 8.

True positive True negative False positive False negative

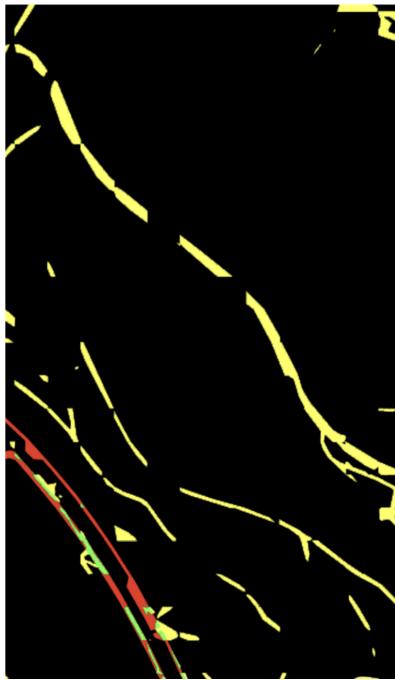


Figure 1.9: Tile2Net - Location 9.

True positive True negative False positive False negative

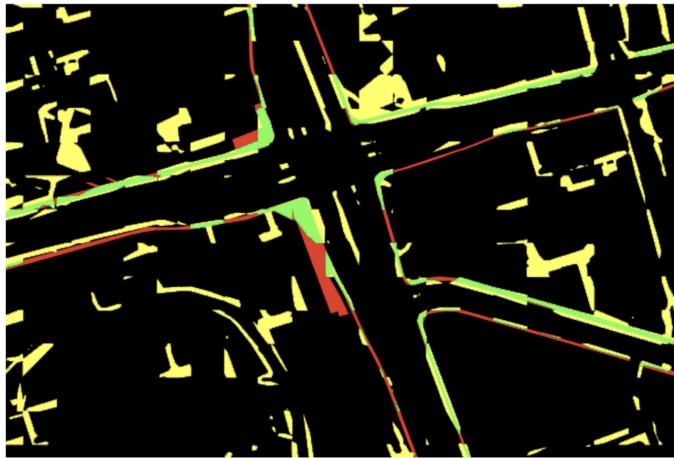


Figure 1.10: Tile2Net - Location 10.

2. Architectural Map Segmentation Results

True positive True negative False positive False negative

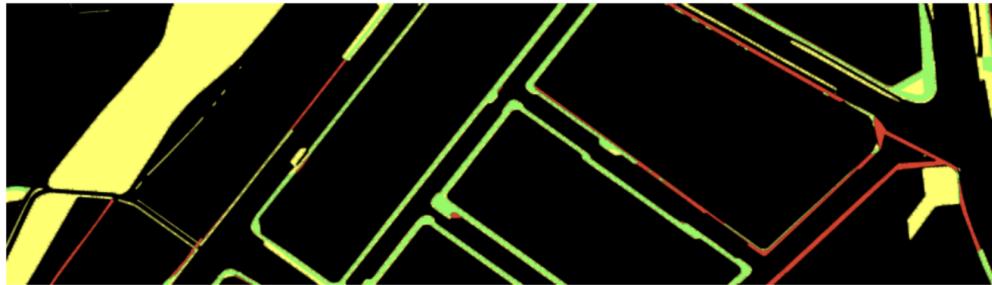


Figure 2.1: AMS - Location 1.

True positive True negative False positive False negative

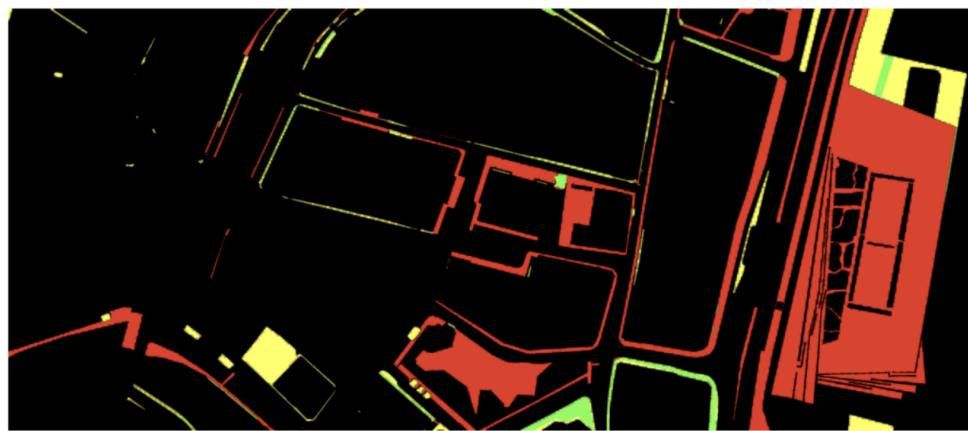


Figure 2.2: AMS - Location 2.

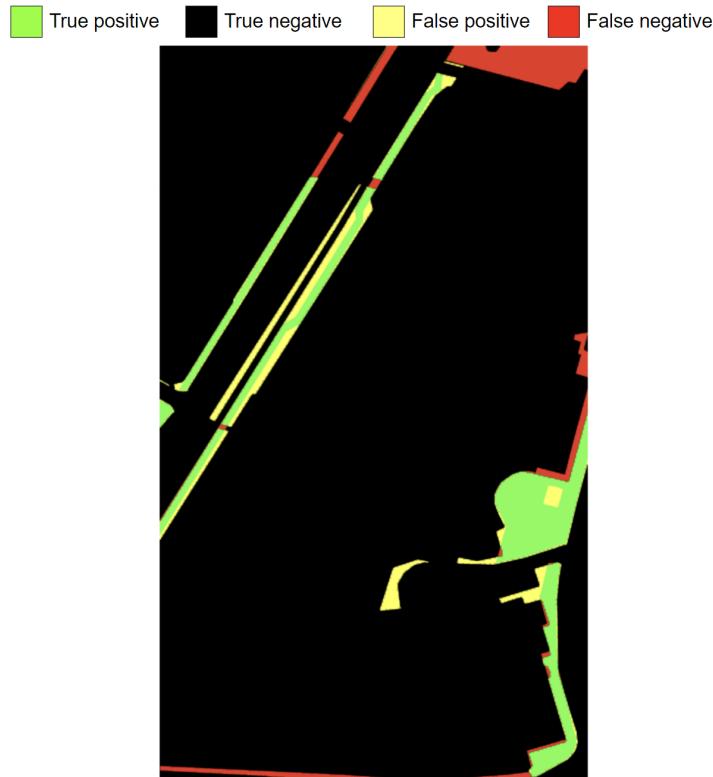


Figure 2.3: AMS - Location 3.

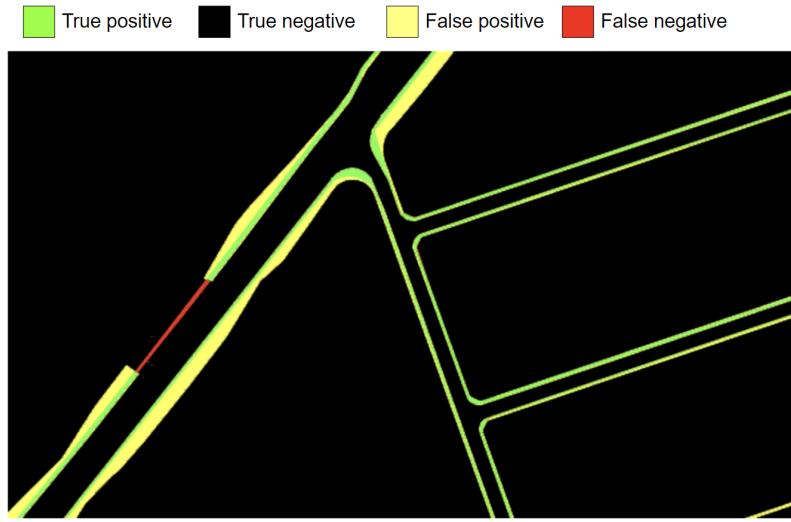


Figure 2.4: AMS - Location 4.

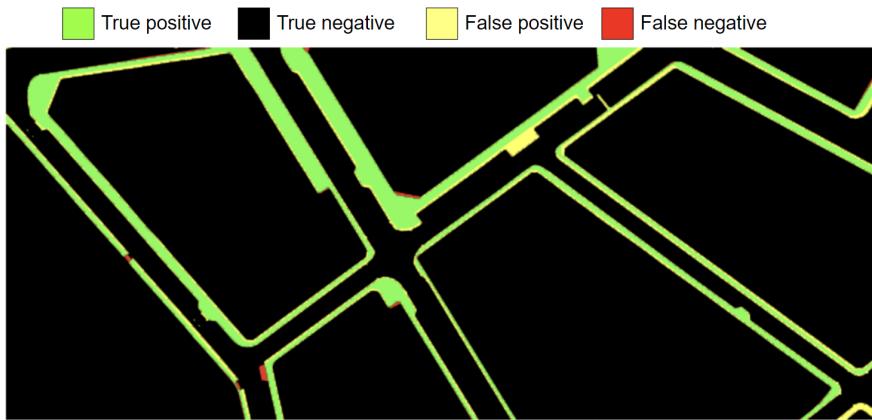


Figure 2.5: AMS - Location 5.

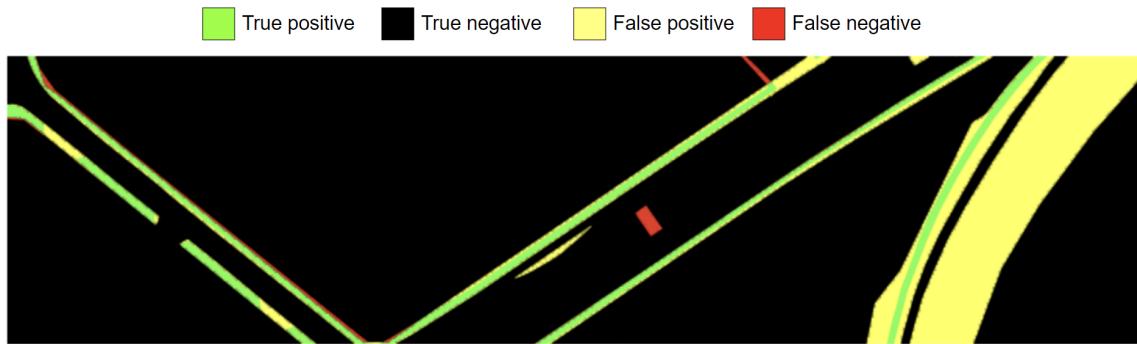


Figure 2.6: AMS - Location 6.

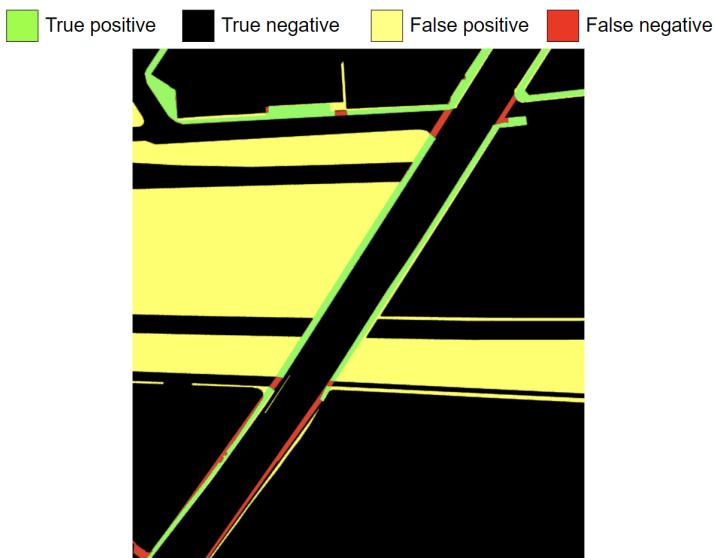


Figure 2.7: AMS - Location 7.



Figure 2.8: AMS - Location 8.

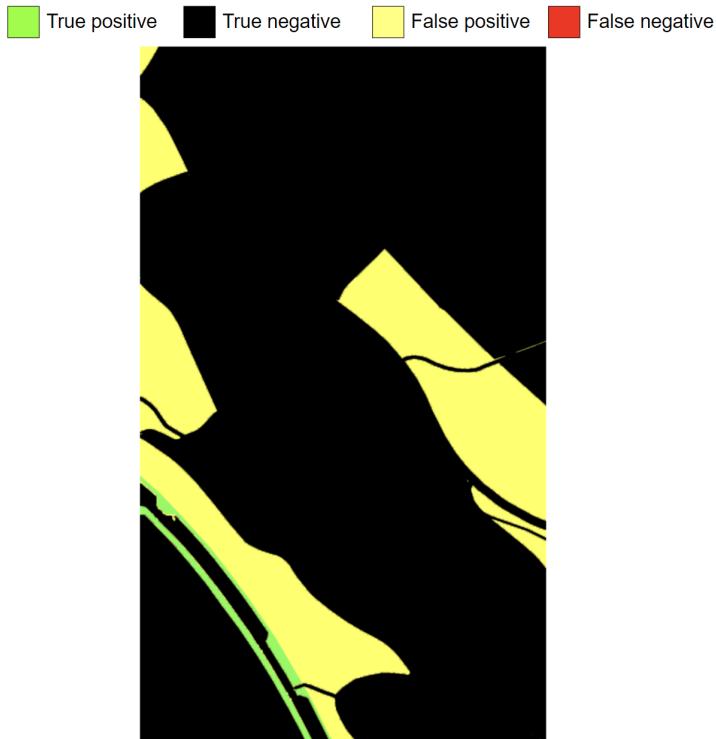


Figure 2.9: AMS - Location 9.

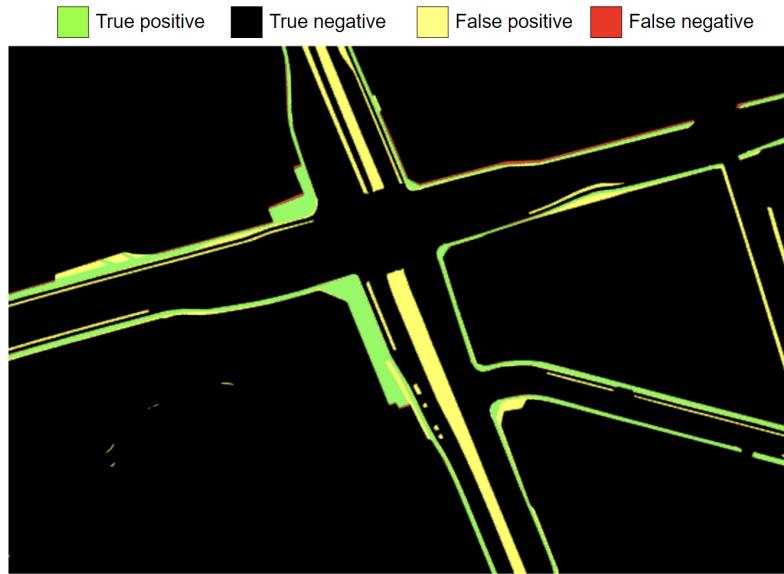


Figure 2.10: AMS - Location 10.