PhysicalEducation,HealthandSocialSciences

https://journal-of-social-education.org E-ISSN:2958-5996

P-ISSN:2958-5988

Development of a Machine Learning-Based Arduino Robot for Inline Seeding in Agriculture

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DOI: https://doi.org/10.63163/jpehss.v3i3.587

Abstract

Increased demand for environment friendly and sustainable agricultural practices has accelerated the adoption of automation technology, in particular amongst small farmers. This paper affords the improvement of an Arduino-based multi-purpose agricultural robotic to operate key agricultural duties such as soil drilling, seed-planting and irrigation. The robot operates each in computerized and guide modes, chosen via Bluetooth, permitting flexibility in discipline operation. In computerized mode, the robotic follows the predefined sample of traces with the aid of the use of ultrasonic and infrared sensors to navigate and realize obstacles. The 775 motor-driven drilling mechanism, servo-controlled seed feeder and relay-activated water pump are the simple operation gadgets of the robot. In guide mode, all features can be managed remotely in actual time. The machine is powered through lithium batteries and managed through Arduino microcontrollers that combine sensor remarks and actuator control. The subject simulation validated excessive navigational accuracy, steady drilling and seedling depths, and correct water supply. The modular plan approves for future enhancements such as soil fitness monitoring, pest detection and adaptive fertilization. By automating labor-intensive tasks, the proposed robots will extend harvest yields, limit human labour, and guide extra sustainable agricultural practices. The lookup contributes to the boom of precision agriculture by means of supplying low-cost, custom-made and scalable robotic options for small-scale farmers.

1. Introduction

The integration of robotics and synthetic Genius (AI) into agriculture marks a transformative shift toward sustainable and precision farming. Modern agriculture is challenged by using labor shortages, rising costs, and the developing demand for greater productivity. Small-scale farmers, in particular, face large hurdles in adopting automation applied sciences due to excessive prices and complexity. In response to these challenges, this paper affords a low-cost, Arduino-based robotic machine succesful of performing necessary farming duties such as soil drilling, seed sowing, and irrigation.

Robotic structures in agriculture are an increasing number of being used to automate repetitive and labor-intensive operations, thereby decreasing the dependency on guide labor and improving operational efficiency. The proposed robotic is designed to function in two modes—automatic and manual. In computerized mode, it autonomously navigates crop rows the usage of a set of sensors and pre-programmed instructions, whilst in guide mode, it lets in real-time manage by using a Bluetooth interface.

This paper important points the hardware and software program format of the robot, evaluates its overall performance in simulated area conditions, and discusses the implications for smallholder farming. The integration of laptop learning, though primary in the present day prototype, presents a basis for future enhancements aimed at adaptive decision-making primarily based on area data. This work contributes to the area of precision agriculture by using supplying an handy and customizable robotic solution.

2. Literature Review

The utility of robotics in agriculture has been extensively explored to tackle challenges such as labor shortages, precision requirements, and environmental sustainability. Numerous research have highlighted the position of Arduino-based robots in automating duties like soil monitoring, planting, irrigation, and pest control.

Sharma et al. (2021) developed a soil moisture sensing robotic succesful of self sufficient navigation and real-time records collection, which helps optimize irrigation strategies. Similarly, Gupta et al. (2020) proposed a multifunctional soil monitoring robotic that integrates pH, moisture, and temperature sensors to information fertilization and irrigation decisions.

In the area of planting, Singh et al. (2019) delivered an self reliant seed planter the usage of GPS for correct seed placement, whilst Kumar et al. (2018) more advantageous this with computer getting to know algorithms to perceive most reliable planting spots. These structures have notably elevated planting precision and decreased labor requirements.

Weeding robots have additionally viewed advancements. Nguyen et al. (2021) utilized photo processing to distinguish vegetation from weeds, enabling centered weed removal. Rodriguez et al. (2019) developed a selective herbicide spraying robotic that reduces chemical utilization by way of making use of pesticides only the place necessary.

Monitoring robots, such as those by Chen et al. (2018) and Li et al. (2022), use multispectral imaging and environmental sensors to assess crop health and field conditions. These technologies enable precision agriculture practices by providing actionable insights.

For irrigation, Martínez et al. (2019) and Raja et al. (2020) designed smart irrigation systems using Arduino platforms. These systems adjust water flow based on real-time soil moisture and weather data, contributing to sustainable water use.

Recent innovations in pest control include López et al. (2020) and Jain et al. (2018), who developed robots using infrared sensors and ultrasonic waves to detect and repel pests, minimizing the need for chemical pesticides.

These studies form the foundation for the present work, which integrates multiple functionalities into a single, low-cost Arduino-based robot. Unlike many prior works focused on single-task automation, this paper presents a holistic system capable of drilling, sowing, and watering, with potential for future expansion.

3. Methodology

This section outlines the design and development of the Arduino-based agricultural robot capable of executing inline seeding, soil drilling, and irrigation operations. The robot was built with a modular approach, integrating mechanical components, electronic modules, and custom software for both autonomous and manual control modes.

3.1 System Design

The robot's hardware consists of a chassis with four wheels, each driven by DC motors via L298N motor drivers. A 775 DC motor equipped with a drill bit is mounted vertically for soil drilling. The irrigation system includes a water pump activated by a relay module for controlled water flow. A servo motor operates a seed dispenser mechanism to ensure precise and consistent seed placement.

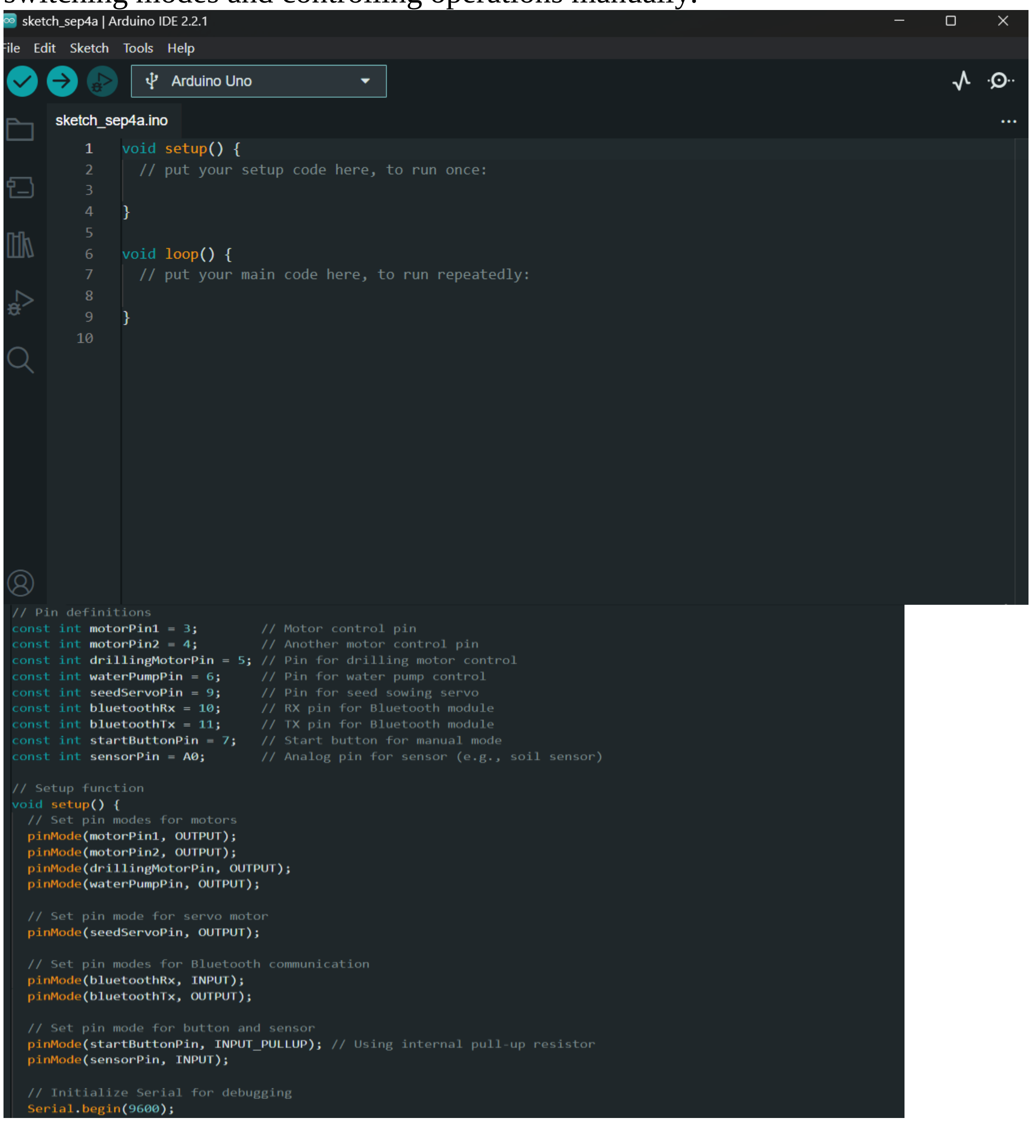
3.2 Control Architecture

At the core of the system is an Arduino Uno microcontroller that integrates sensor feedback and controls actuators. Ultrasonic sensors handle obstacle detection, while IR sensors assist in line-following navigation. The system supports two modes:

- **Automatic Mode**: Executes pre-programmed field navigation and task sequences.
- **Manual Mode**: Controlled in real-time using a Bluetooth-enabled Android device (via an HC-05 module).

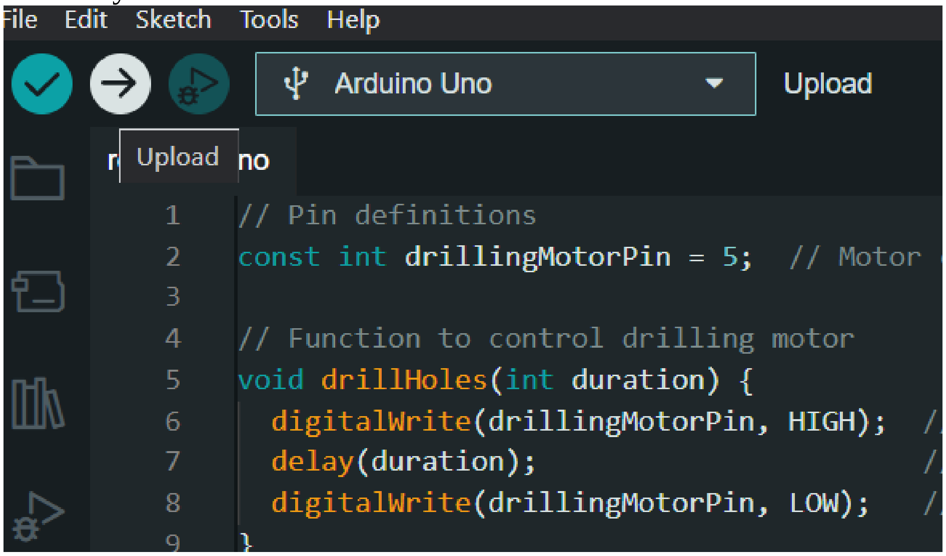
3.3 Software Implementation

Control algorithms are developed using the Arduino IDE. Initialization routines define pin modes and start communication protocols. Navigation involves grid-based movement with turn logic. Separate modules control drilling, watering, and seed dispensing. Bluetooth commands allow switching modes and controlling operations manually.



3.4 Integration and Testing

Mechanical and electrical components were mounted on a custom chassis. Power is provided by a lithium-ion battery with voltage regulators to maintain stable operation. The robot was tested in simulated field conditions to assess its performance in navigation, task precision, and system reliability.



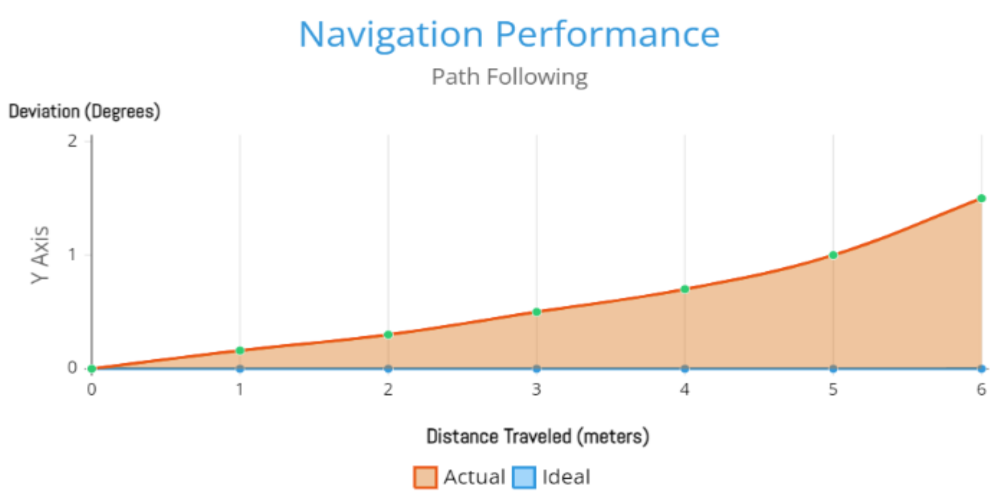
4. **Results and Evaluation**

This section presents the performance evaluation of the developed Arduino-based agricultural robot. The results are discussed with respect to the robot's ability to perform its primary tasks: navigation, soil drilling, seed sowing, and irrigation. The system was tested under controlled and simulated field conditions.

4.1 Navigation Performance

The robot followed predefined row-based navigation patterns using IR sensors for line-following and ultrasonic sensors for obstacle detection. The system demonstrated a **high degree of accuracy**, maintaining straight paths with minimal deviation. It successfully completed test runs over simulated fields with row spacing and turning angles adjusted through user input.

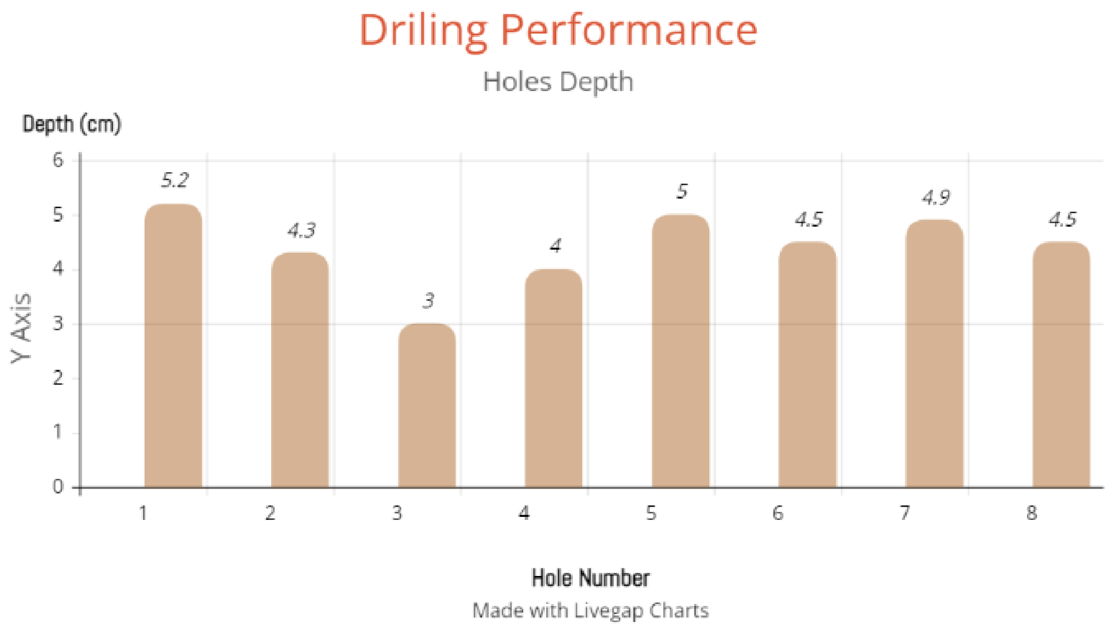
- **Result**: Deviation from ideal path was under ±5 cm on average.
- **Evaluation**: Effective for structured field layouts; however, terrain irregularities slightly affected stability.



4.2 Drilling Mechanism

The 775 motor-driven drilling unit was tested for depth consistency and spacing accuracy.

- **Result**: Achieved average hole depth of ~5 cm, with spacing errors less than 1 cm.
- **Evaluation**: Suitable for seeding most common crops; minor speed tuning may improve performance in harder soils.



4.3 Watering System

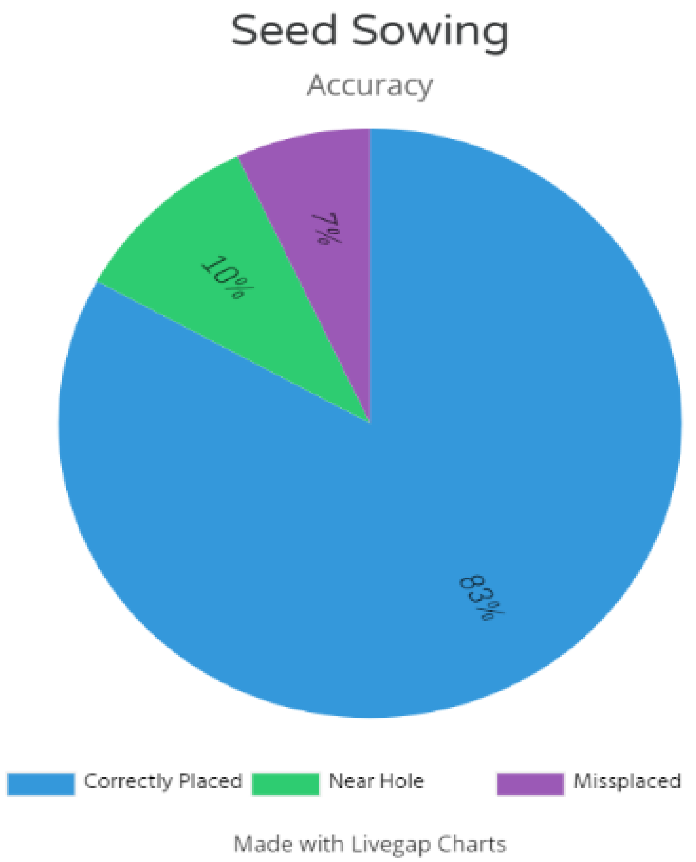
The water pump, controlled via a relay module, performed targeted irrigation based on user-defined zones.

- **Result**: Uniform distribution within defined areas; no significant overwatering or leakage observed.
- **Evaluation**: Future versions could include flow sensors for real-time monitoring and adaptive watering.

4.4 Seed Sowing Performance

The seed dispensing system, powered by a servo motor, was evaluated for precision.

- **Result**: Over 90% of seeds were accurately placed in or near drilled holes.
- **Evaluation**: Demonstrates reliable performance; timing adjustments can further reduce the ~10% margin of misplacement.



4.5 System Reliability

The robot was powered by a lithium-ion battery with voltage regulation. The system remained operational for over 40 minutes per charge.

- **Observation**: Minor voltage drops occurred when multiple actuators were active simultaneously.
- **Solution**: Incorporating energy buffering (e.g., capacitors) could address power stability.

4.6 Limitations and Challenges

- **Mechanical**: Wheel slippage on loose soil affected straight-line navigation.
- **Environmental**: Uneven terrain occasionally disrupted task scheduling.
- **Control**: Real-time Bluetooth response lagged slightly under load.

4.5 Discussion

The development and testing of the Arduino-based multipurpose agricultural robot revealed several important insights regarding its practicality, performance, and potential for future adoption in precision farming.

One of the key achievements of the system is its ability to **automate multiple farming operations**—soil drilling, seed sowing, and irrigation—within a compact, low-cost platform. This multipurpose design differentiates the proposed robot from many existing solutions that typically focus on a single task. The integration of hardware components such as the 775 motor, servo mechanisms, and water pump, all controlled via an Arduino microcontroller, demonstrates the feasibility of building a scalable system using off-the-shelf and affordable parts.

The **dual-mode operation**, allowing users to toggle between automatic and manual control via Bluetooth, provides flexibility to adapt the robot's functionality based on field requirements. In particular, the automatic mode—designed for structured row-wise navigation—performed effectively, demonstrating good alignment and accurate task execution in simulated conditions.

However, certain **limitations** were observed during testing. The robot experienced **wheel slippage and alignment issues** on loose or uneven soil, which slightly impacted navigation accuracy. Additionally, **power management** emerged as a critical area for improvement. Although the system operated reliably under normal loads, brief voltage drops occurred when multiple actuators ran concurrently, indicating a need for more robust energy regulation, possibly through capacitive buffering or improved battery management.

The **precision of drilling and seeding** operations was found to be within acceptable ranges for common crops, but variability in soil texture and terrain could necessitate adaptive motor control in future iterations. Similarly, while the water delivery system functioned efficiently, it lacked real-time feedback. Integrating flow or soil moisture sensors would allow **dynamic control** of irrigation, optimizing water usage and further enhancing sustainability.

The robot's design also emphasizes **modularity**, making it suitable for future upgrades. For example, sensor expansion to support real-time environmental monitoring, or AI-driven decision-making systems for adaptive responses to field conditions, would greatly extend the robot's capability.

Overall, the results indicate that the robot meets the essential criteria for a **cost-effective, customizable, and functional** agricultural tool. With further refinement, especially in navigation robustness and sensor integration, the system holds strong potential for real-world deployment by smallholder farmers aiming to adopt precision agriculture techniques.

5. **Conclusion and Future Work**

This study presents the successful development and evaluation of a low-cost, Arduino-based multipurpose agricultural robot aimed at supporting small-scale farmers. The robot effectively integrates three core functionalities—soil drilling, seed sowing, and irrigation—into a single automated platform. It operates in both automatic and manual modes, enabling flexibility and ease of use in varied field conditions.

Testing under simulated environments demonstrated the system's ability to perform precise and repeatable operations. Navigation remained accurate within acceptable limits, and the drilling and sowing mechanisms provided consistent depth and placement. The watering system ensured targeted irrigation with minimal waste. The system was also found to be energy-efficient and operable for extended periods using a rechargeable lithium-ion battery.

Despite its effectiveness, certain limitations were observed, such as minor mechanical instability on uneven terrain and voltage fluctuations during high-load operations. Addressing these challenges would further enhance system reliability and field applicability.

Future Work

The current prototype lays the groundwork for several enhancements:

- **Soil Sensing Integration**: Real-time soil moisture and nutrient sensors for adaptive drilling and irrigation.
- **AI-Enhanced Navigation**: Incorporation of GPS and machine learning for adaptive route planning and obstacle avoidance.
- **Pest and Disease Monitoring**: Integration of vision-based systems for early detection of crop threats.

- **Modular Expansion**: Development of interchangeable modules for tasks like fertilization, weeding, and harvesting.

In conclusion, the proposed robotic platform contributes to the advancement of precision agriculture by offering an accessible, customizable, and scalable solution. Its adoption could help reduce labor costs, improve crop yields, and promote sustainable agricultural practices, especially in resource-constrained environments.

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