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Multipurpose Agricultural Robot Using GPS, Computer Vision, and Modular Mechanisms for Smart Farming

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Abstract: *The rapid growth in global population and the increasing demand for food production have created significant challenges for the agricultural sector. Traditional farming methods, which rely heavily on manual labor and excessive resource usage, are no longer sufficient to meet these demands efficiently. This paper presents the design and implementation of a multipurpose agricultural robot capable of performing three essential farming operations: ploughing, seeding, and spraying.*

The proposed system is developed as a compact, energy-efficient robotic platform equipped with a modular mechanism that allows easy switching between different tools. It integrates advanced navigation technologies such as Global Positioning System (GPS) and Inertial Measurement Units (IMU) for accurate movement, along with proximity sensors for obstacle detection and safe operation. The seeding unit ensures proper placement of seeds at controlled depth and spacing, improving crop growth and minimizing wastage. The spraying mechanism is designed for precise application of fertilizers and pesticides, with the potential for future enhancement using image-based crop analysis for targeted spraying. Additionally, the ploughing system prepares the soil effectively, ensuring better aeration and seedbed quality.

The implementation of this robot reduces human effort, optimizes resource utilization, and minimizes environmental impact. Although challenges such as cost and technical complexity exist, the system demonstrates strong potential for improving agricultural productivity and supporting sustainable farming practices. This work highlights the role of automation and robotics as key enablers in the transformation of conventional agriculture into smart and precision-based farming.

Keywords*:* Precision Agriculture, Agricultural Robot, Automation, GPS Navigation, Smart Farming, Seeding Mechanism, Spraying System, Ploughing, Sustainable Agriculture, Robotics in Agriculture

I. INTRODUCTION

Agriculture has long been the backbone of human civilization, playing a crucial role in sustaining livelihoods and ensuring food security. However, the sector is currently facing unprecedented challenges due to rapid population growth, climate variability, declining natural resources, and labor shortages. It is projected that global food production must increase significantly to meet the demands of a growing population by 2050 [1]. Traditional farming practices, which largely depend on manual labor and generalized input application, are becoming inefficient, resource-intensive, and environmentally unsustainable [2]. These limitations necessitate the adoption of advanced technologies to improve productivity and efficiency.

In recent years, precision agriculture has emerged as a transformative approach that focuses on the optimized use of inputs such as water, fertilizers, and pesticides. This method relies on data-driven decision-making and site-specific crop management to enhance yield while minimizing environmental impact [3]. The integration of automation and robotics into agriculture has further accelerated this transformation. Agricultural robots, also known as agribots, are capable of performing repetitive and labor-intensive tasks with higher accuracy and consistency compared to traditional methods [4].

One of the major concerns in agriculture is the excessive use of chemicals during spraying operations, which leads to environmental pollution and health hazards. Studies have shown that conventional spraying methods often result in significant wastage, with a large portion of chemicals not reaching the intended target [5]. Similarly, improper seeding techniques can lead to uneven crop growth, reduced germination rates, and inefficient use of seeds [6]. Soil preparation through conventional plugging methods also contributes to soil compaction and degradation, negatively affecting soil fertility over time [7]. These issues highlight the need for an integrated solution that can perform multiple farming operations with precision and minimal resource wastage.

Autonomous robotic systems offer a promising solution to these challenges. With the advancement of technologies such as the Global Positioning System (GPS), Inertial Measurement Units (IMU), and various sensing devices, robots can navigate agricultural fields with high accuracy and reliability [8]. Additionally, the incorporation of computer vision and machine learning techniques enables robots to identify crops, weeds, and soil conditions, allowing for targeted and intelligent operations [9]. These capabilities not only improve operational efficiency but also reduce the environmental footprint of farming activities.

This paper proposes the design and development of a multipurpose agricultural robot that integrates ploughing, seeding, and spraying functionalities into a single platform. Unlike conventional systems that require separate machinery for each task, the proposed robot utilizes a modular design that allows seamless switching between different operations. The system is designed to operate autonomously or semi-autonomously, reducing the dependency on human labor while ensuring precision and consistency in field operations. The integration of advanced navigation and sensing technologies further enhances the robot's performance in dynamic agricultural environments [10].

II. PROBLEM STATEMENT

The agricultural sector is currently confronted with a combination of critical challenges that hinder productivity, efficiency, and sustainability. Rapid population growth has significantly increased the demand for food, placing pressure on farmers to produce higher yields from limited and often declining arable land. At the same time, traditional farming methods remain heavily dependent on manual labor and conventional machinery, which are not only time-consuming and labor-intensive but also lack precision in execution. The growing shortage of agricultural labor, especially in rural areas, further complicates timely farm operations such as ploughing, seeding, and spraying. In addition, improper seeding techniques often result in uneven crop distribution and reduced germination rates, while conventional spraying practices lead to excessive and non-uniform application of fertilizers and pesticides, causing resource wastage, increased production costs, and environmental pollution. Heavy machinery used in traditional ploughing contributes to soil compaction, adversely affecting soil health and long-term productivity. Moreover, the absence of integrated technological solutions forces farmers to rely on multiple machines for different operations, increasing both capital investment and operational complexity. These issues highlight the urgent need for a unified, efficient, and automated system capable of performing multiple agricultural tasks with high precision, optimized resource utilization, reduced human effort, and minimal environmental impact, thereby supporting the transition towards sustainable and smart farming practices.

III. OBJECTIVE

- To design and develop a multipurpose agricultural robot capable of performing essential farming operations such as ploughing, seeding, and spraying within a single integrated system.
- To reduce dependency on manual labor by automating repetitive and labor-intensive agricultural tasks, thereby improving efficiency and saving time.

- To achieve precision in farming operations by ensuring accurate seed placement, controlled spraying of fertilizers and pesticides, and uniform soil preparation.
- To optimize the use of agricultural resources such as seeds, water, and chemicals, minimizing wastage and reducing overall farming costs.
- To promote sustainable and eco-friendly farming practices by reducing environmental impact through efficient input usage and minimizing soil degradation

IV. LITERATURE SURVEY

1. Paper Title: Agricultural Robots for Field Operations: Concepts and Components
Year: 2016
Authors: A. Bechar, C. Vigneault
Journal: Biosystems Engineering
Summary: This paper provides a comprehensive overview of agricultural robots designed for various field operations such as planting, spraying, and harvesting. The authors discuss the fundamental components required for building agricultural robots, including navigation systems, sensing technologies, actuators, and control units. The study emphasizes the importance of integrating Global Positioning Systems (GPS), machine vision, and automation technologies to improve accuracy and efficiency in farming operations. It highlights how robotic systems can reduce human effort while increasing productivity in modern agriculture.

Furthermore, the paper explains the challenges associated with implementing agricultural robots, such as environmental variability, high system costs, and technical limitations. It also discusses the need for robust design and adaptability in field conditions. The research concludes that agricultural robotics has significant potential to revolutionize farming practices by enabling precision agriculture and reducing dependency on manual labor, making it highly relevant to the development of multipurpose agricultural robots.

2. Paper Title: Autonomous Robotic Weed Control Systems: A Review
Year: 2008
Authors: D. C. Slaughter, D. K. Giles, D. Downey
Journal: Computers and Electronics in Agriculture
Summary: This paper reviews the development of autonomous systems for weed control in agriculture. It focuses on different techniques used for detecting and removing weeds, including machine vision, spectral analysis, and sensor-based systems. The authors highlight that conventional weed control methods rely heavily on blanket spraying, which leads to excessive use of herbicides and environmental pollution. The study emphasizes the importance of automated systems that can identify weeds and apply treatment only where necessary.

In addition, the paper discusses the integration of robotics and artificial intelligence in improving weed management practices. It explains how image processing and pattern recognition techniques can be used to differentiate between crops and weeds. The findings demonstrate that automated weed control systems can significantly reduce chemical usage and improve sustainability. This research strongly supports the concept of targeted spraying in multipurpose agricultural robots.

3. Paper Title: A Review of Computer Vision Technologies in Precision Agriculture
Year: 2025
Authors: Wenqi Wang, Ye Kang
Journal: Engineering and Applied Science Journal
Summary: This paper explores the application of computer vision technologies in precision agriculture, focusing on the use of deep learning models such as Convolutional Neural Networks (CNNs) for crop monitoring, disease detection, and weed identification. The study highlights the role of advanced algorithms like YOLO, ResNet, and

SegNet in improving detection accuracy and enabling real-time decision-making in agricultural environments. It also discusses the integration of sensors, drones, and IoT devices with vision systems to enhance data collection and analysis.

The authors further explain that computer vision-based systems have significantly improved the efficiency of precision farming by enabling targeted interventions. These technologies help reduce the overuse of chemicals and optimize resource utilization. However, challenges such as data variability, environmental conditions, and computational requirements are also discussed. The paper concludes that computer vision plays a vital role in developing intelligent agricultural robots capable of performing automated tasks like spraying and monitoring**.**

4. Paper Title: Automated Weed Detection for Sustainable Agriculture Using CNN and Image Processing
Year: 2021
Authors: K. Uthra Devi, S. Tamil, N. Vaijayanthi, M. Bhuvaneshwari, P. Subharajam
Journal: International Journal of Intelligent Systems and Applications in Engineering
Summary: This paper presents a smart weed detection system based on Convolutional Neural Networks (CNN) and image processing techniques. The system uses a trained model to identify weeds in real-time using images captured from agricultural fields. The authors highlight that traditional weed control methods are inefficient and harmful to the environment due to excessive herbicide use. The proposed system aims to overcome these limitations by providing accurate weed detection**.**

Additionally, the paper discusses the implementation of the system on embedded platforms such as Raspberry Pi, making it suitable for real-time applications. The results show that CNN-based models can achieve high accuracy in distinguishing crops from weeds, enabling precise and targeted spraying. This research directly supports the integration of AI-based spraying systems in agricultural robots, improving efficiency and sustainability.

5. Paper Title: Real-Time Semantic Segmentation of Crop and Weed for Precision Agriculture Robots
Year: 2017
Authors: A. Milioto, P. Lottes, C. Stachniss
Journal: Journal of Field Robotics
Summary: This paper introduces a real-time semantic segmentation approach for distinguishing crops and weeds using Convolutional Neural Networks. The system processes RGB images to classify different elements in the field, enabling robots to perform selective weed control. The authors demonstrate that their model can operate efficiently in real-time conditions and adapt to different agricultural environments.

Moreover, the study highlights the importance of accurate classification for precision agriculture applications. The system is capable of learning from small datasets and generalizing across various field conditions. The research proves that real-time image processing and machine learning can significantly enhance the performance of agricultural robots, particularly in targeted spraying and weed management**.**

6. Paper Title: Comparative Evaluation of CNN Models for Precision Agriculture in Deep Learning-Based Weed Detection
Year: 2024
Authors: K. Mohanappriya, C. Vennila, R. Roshan Joshua, A. T. Barani Vijaya Kumar
Journal: Journal of Neonatal Surgery
Summary: This paper evaluates different deep learning models, including DenseNet, ResNet, and VGGNet, for weed detection in agricultural fields. The authors compare the performance of these models based on accuracy, precision, and recall using real-time datasets. The study highlights that deep learning techniques play a crucial role in improving the effectiveness of precision agriculture systems.

The results show that DenseNet outperforms other models in terms of accuracy, making it more suitable for real-time agricultural applications. The paper emphasizes the importance of selecting appropriate models for efficient weed detection and targeted spraying. This research contributes to the development of intelligent agricultural robots by providing insights into model selection and performance optimization..

V. PROPOSED SYSTEM

The proposed system focuses on the design and development of a multipurpose agricultural robot capable of performing three essential farming operations—ploughing, seeding, and spraying—within a single integrated platform. The system is designed to support precision agriculture by improving operational accuracy, reducing human effort, and optimizing the use of resources. Unlike conventional farming methods that require separate machines for each activity, the proposed robot utilizes a modular architecture that allows different tools to be attached or detached easily based on the required operation. This approach not only minimizes equipment cost but also enhances flexibility and usability for small and medium-scale farmers.

A. System Overview

The system consists of a mobile robotic platform equipped with a robust chassis, drive mechanism, control unit, sensor suite, and interchangeable tool modules. The robot operates either autonomously or in a semi-autonomous mode, where the user can input field parameters such as boundaries, crop type, and operational settings. Based on this input, the robot generates an optimized path to cover the entire field efficiently. The integration of navigation technologies such as GPS and IMU enables accurate movement, while proximity sensors ensure safe operation by detecting obstacles in real time.

The robot is powered by a rechargeable battery system, which ensures eco-friendly operation with minimal dependence on fossil fuels. Additionally, the system is designed to support future enhancements such as solar charging and IoT-based remote monitoring. The compact design and lightweight structure reduce soil compaction and make the robot suitable for various types of agricultural fields.

B. Mechanical Design and Modular Structure

The mechanical structure of the robot is designed to provide strength, stability, and adaptability in different field conditions. The chassis is fabricated using lightweight yet durable materials such as aluminum or mild steel. The robot is supported by four or six wheels with high-traction tires to ensure smooth movement on uneven terrain. The drive system includes DC motors connected to motor drivers, enabling controlled motion in forward, reverse, and turning directions.

A key feature of the proposed system is its modular tool attachment mechanism. This mechanism allows the robot to switch between ploughing, seeding, and spraying units without complex reconfiguration. Each module is designed as an independent unit that can be easily mounted onto the robot. The ploughing module consists of a rotary tiller for soil preparation, the seeding module includes a seed hopper and dispensing system, and the spraying module comprises a tank, pump, and nozzle assembly. This modularity ensures versatility and reduces the need for multiple machines.

C. Navigation and Control System

The navigation system is a critical component that enables the robot to operate autonomously with high precision. It combines data from GPS for global positioning and IMU sensors for orientation and stability. This combination allows the robot to follow predefined paths accurately even in uneven terrain. For short-range obstacle detection, ultrasonic sensors and LiDAR are used to identify and avoid obstacles such as rocks, animals, or humans in the field.

The control system is managed by an onboard microcontroller or embedded computing unit, such as a Raspberry Pi or similar platform. It processes sensor data, executes navigation algorithms, and controls the movement of the robot as well as the operation of different modules. The system uses path planning algorithms to ensure complete field coverage with minimal overlap. A user interface, either through a mobile application or remote controller, allows the farmer to monitor and control the robot's operations easily.

D. Working Mechanism of Functional Modules

The proposed robot operates in three primary modes, each corresponding to a specific agricultural function. In the ploughing mode, the rotary tiller attached to the robot loosens the soil to a desired depth, improving soil aeration and preparing it for planting. The robot maintains a constant speed and depth to ensure uniform soil preparation across the field.

In the seeding mode, the robot uses a precision seed dispensing mechanism to place seeds at uniform intervals and controlled depth. This ensures optimal plant spacing, which is essential for healthy crop growth and maximum yield. The system can be adjusted based on different crop requirements, making it suitable for a variety of farming applications**.**

In the spraying mode, the robot applies fertilizers or pesticides using a controlled spraying system. The liquid is stored in a tank and delivered through nozzles using a pump. The system can be further enhanced with camera-based detection to identify weeds or affected areas, enabling targeted spraying. This reduces chemical usage and minimizes environmental impact while maintaining crop health.

E. Advantages of the Proposed System

The proposed system offers several advantages over traditional farming methods. It significantly reduces manual labor and operational time by automating multiple tasks. The precision achieved in seeding and spraying leads to better crop growth and reduced input wastage. The lightweight design minimizes soil compaction, preserving soil health and fertility. Additionally, the modular approach makes the system cost-effective and adaptable to different farming needs.

Overall, the proposed multipurpose agricultural robot provides a smart, efficient, and sustainable solution for modern agriculture. It bridges the gap between traditional practices and advanced technologies, paving the way for the adoption of precision farming techniques on a wider scale..

SYSTEM DESIGN

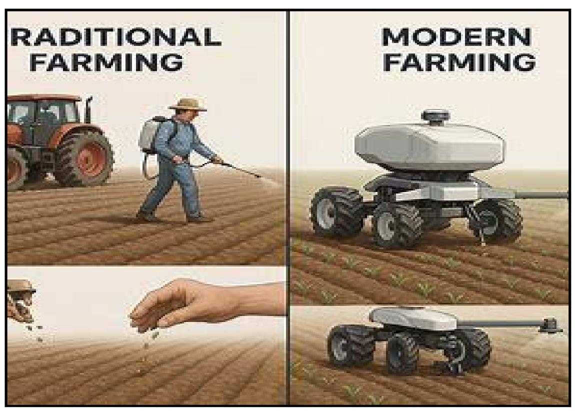

Fig 1: System Architecture

The overall system architecture is designed as an integrated framework that combines mechanical, electrical, and software components into a single functional unit. The robot operates as a closed-loop system where sensor inputs are continuously processed by the control unit to make real-time decisions. The architecture includes key modules such as the power supply unit, control system, sensor array, drive mechanism, and interchangeable tool attachments. All these components are interconnected to ensure smooth coordination and efficient task execution.

The design emphasizes modularity and scalability, allowing additional features or components to be incorporated in the future without major redesign. The system is also designed to support both autonomous and semi-autonomous modes of operation. In autonomous mode, the robot follows predefined paths using navigation algorithms, while in semi-autonomous mode, the user can control and monitor operations remotely. This flexibility enhances usability and makes the system adaptable to different farming conditions.

A. Overall System Architecture

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B. Mechanical System Design

The mechanical system forms the physical backbone of the robot and is responsible for providing structural support and mobility. The chassis is designed using lightweight yet durable materials such as aluminum or mild steel to withstand harsh agricultural environments. It is engineered to maintain balance and stability while carrying different modules and operating on uneven terrain. The wheel configuration, typically consisting of four or six wheels, ensures proper traction and smooth movement across soil surfaces.

In addition to the chassis, the mechanical design includes a modular attachment system for implementing different agricultural tools. This system allows easy installation and removal of ploughing, seeding, and spraying units. The ploughing mechanism uses rotating blades for soil tilling, while the seeding mechanism includes a controlled dispensing system. The spraying unit consists of a tank, pump, and nozzle assembly. The entire mechanical system is designed to minimize soil compaction and maximize operational efficiency.

C. Electrical and Power System Design

The electrical system is responsible for powering all components of the robot and ensuring their coordinated operation. The robot is powered by a rechargeable battery, typically lithium-ion, which provides sufficient energy for extended field operations. The power distribution system is designed to supply stable voltage and current to motors, sensors, control units, and actuators. Voltage regulators and protection circuits are included to prevent damage due to fluctuations or overload.

The system also includes motor drivers that control the speed and direction of the drive motors as well as the operation of functional modules. Energy efficiency is a key consideration in the design, and provisions can be made for integrating renewable energy sources such as solar panels. The electrical layout is organized to reduce power loss and ensure reliable performance, even under continuous usage in field conditions.

D. Sensor and Navigation System Design

The sensor and navigation system enables the robot to move accurately and safely within the agricultural field. The primary navigation component is the GPS module, which provides location data for path planning and field coverage. This is complemented by an Inertial Measurement Unit (IMU) that tracks orientation and motion, ensuring stability and accurate direction control, especially on uneven surfaces.

For obstacle detection and avoidance, the system uses ultrasonic sensors and LiDAR technology. These sensors continuously monitor the surroundings and help the robot avoid collisions with obstacles such as rocks, plants, or humans. The integration of multiple sensors improves reliability through sensor fusion, allowing the system to make better decisions based on combined data inputs. This design ensures safe and efficient navigation in dynamic environments.

E. Control System and Software Design

The control system acts as the brain of the robot, managing all operations and coordinating between different subsystems. It is implemented using a microcontroller or embedded processor such as a Raspberry Pi. The control unit processes data from sensors, executes navigation algorithms, and sends control signals to motors and actuators. The system operates using programmed logic that enables the robot to perform tasks autonomously with minimal human intervention.

The software design includes modules for path planning, obstacle avoidance, and task execution. Advanced algorithms are used to ensure complete field coverage while minimizing overlap and energy consumption. The system can also incorporate machine learning techniques for tasks such as weed detection and targeted spraying. A user interface is provided for inputting parameters and monitoring system performance, making the robot user-friendly and efficient.

F. Functional Module Design

The functional modules are the core components that perform specific agricultural operations. The ploughing module is designed with rotating blades that penetrate and loosen the soil to a controlled depth. This improves soil aeration and prepares the land for planting. The design ensures uniform soil treatment across the field.

The seeding module consists of a hopper and a dispensing mechanism that releases seeds at precise intervals and depth. This ensures optimal plant spacing and improves crop yield. The spraying module includes a liquid tank, pump, and nozzles for applying fertilizers or pesticides. The system can be enhanced with camera-based detection to enable targeted spraying, reducing chemical usage and environmental impact. Each module is designed to operate efficiently while being easily interchangeable within the overall system.

VI. RESULT

This image showcases a multifunctional agricultural robot or autonomous rover prototype, designed for small-scale farming or soil management tasks. The vehicle is built on a robust four-wheeled chassis featuring large, high-traction treaded tires, which are essential for navigating uneven or soft terrain commonly found in garden beds or fields. Its low-slung profile suggests a focus on stability while carrying various mechanical and liquid payloads.

Fig 2: System Model

The most prominent feature is a clear cylindrical reservoir with a blue lid mounted centrally on the chassis. A flexible plastic tube extends from this tank, leading toward a small electric water pump positioned at the front of the vehicle. This configuration indicates that the robot is equipped for precision liquid application, such as automated watering, liquid fertilization, or targeted pesticide spraying, directly integrated into its movement path.

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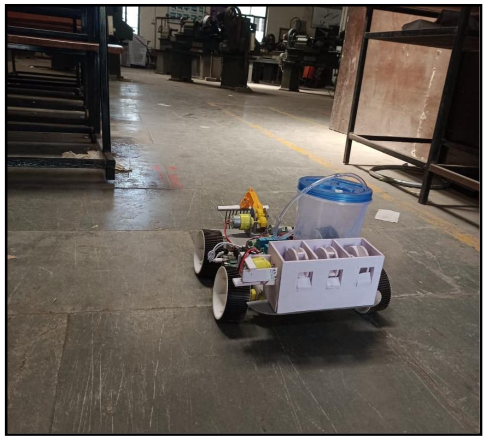

Fig 3: cylindrical reservoir

At the very front, the robot features a specialized mechanical attachment: a miniature rake or harrow. This tool is connected to a bright orange actuator arm, which likely provides the leverage needed to tilt or lower the rake into the soil. This component is designed for light tillage, soil aeration, or debris clearing, allowing the robot to prepare the ground surface simultaneously as it performs other maintenance tasks.

The "brain" of the operation is visible behind the water tank, consisting of a green electronic circuit board and a relay module. These components manage the power distribution and logic for the drive motors, the pump, and the actuator arm. The presence of multiple wires and connectors highlights the prototype's complexity, suggesting it can be programmed or remotely controlled to execute specific sequences of soil treatment and irrigation.

A secondary high-torque DC motor is mounted near the front axle to drive the mechanical arm, while separate motors likely power each of the four wheels for independent or differential steering. The use of standard industrial components and 3D-printed or custom-fabricated brackets shows a high degree of engineering intent, aimed at creating a versatile tool that can replace manual labor in repetitive agricultural chores.

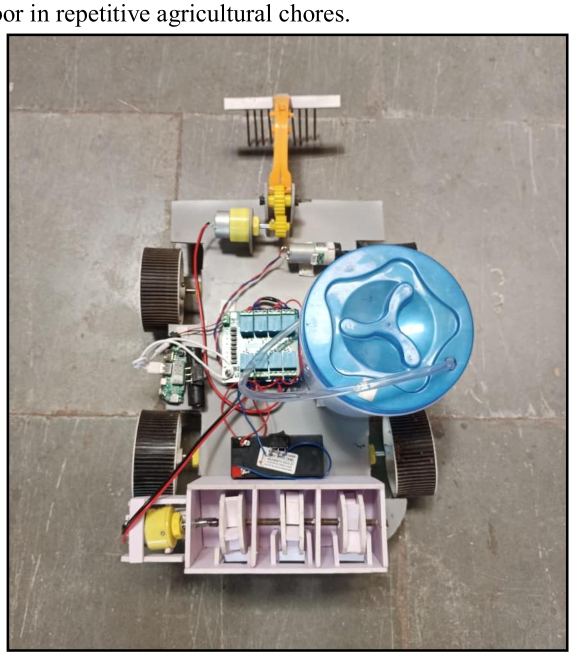

Fig 4: Integrated Precision Farming Rover

The entire assembly rests on a stone-tiled floor, likely within a laboratory, workshop, or exhibition space. The background reveals an open-air or industrial environment, which fits the context of testing a machine built for outdoor endurance. This prototype represents a convergence of robotics and smart farming, utilizing automated systems to optimize resource use and improve soil health through mechanical and chemical means.

The prominent blue-capped tank serves as the main chemical or water storage unit. It is connected via a transparent siphon tube to a small DC-powered pump located near the front-left axle. This "on-demand" irrigation system allows the rover to provide targeted hydration to crops, minimizing water waste. By placing the tank toward the rear-center, the weight is distributed over the back wheels, providing better traction for the front-mounted mechanical attachments.

Soil Aeration and Tillage Module: At the front of the rover, a bright orange mechanical arm operates a miniature rake. This module is powered by a dedicated high-torque yellow geared motor, visible just behind the rake's pivot point. This system is designed to break up surface crust and aerate the soil, which improves water penetration and oxygen flow to the roots. The gear-driven mechanism allows the rake to be raised or lowered depending on the soil conditions and the specific mission phase.

VII. CONCLUSION

The development of a multipurpose agricultural robot integrating ploughing, seeding, and spraying functions presents a practical and forward-looking solution to the challenges faced in modern agriculture. This system demonstrates how automation and precision-based technologies can significantly improve farming efficiency while reducing dependency on manual labor. By combining multiple essential operations into a single platform, the robot minimizes the need for separate machinery, thereby lowering operational complexity and overall cost in the long run.

The proposed design emphasizes accuracy, resource optimization, and environmental sustainability. Precise seed placement, controlled spraying, and uniform soil preparation contribute to better crop growth and higher productivity. At the same time, the reduction in excessive use of fertilizers and pesticides helps in preserving soil health and minimizing environmental impact. Although certain challenges such as initial investment and technical maintenance remain, the long-term benefits of improved efficiency, reduced input wastage, and enhanced safety make this system highly valuable.

In conclusion, the multipurpose agricultural robot represents an important step toward the adoption of smart farming practices. It not only addresses current agricultural limitations but also lays the foundation for future advancements in autonomous farming systems. With further improvements and wider accessibility, such technologies have the potential to transform traditional agriculture into a more efficient, sustainable, and technology-driven sector..

FUTURE SCOPE

The proposed multipurpose agricultural robot offers significant potential for further development and enhancement to meet the evolving demands of modern farming. One important area of future work is the integration of advanced artificial intelligence and machine learning algorithms to enable more intelligent decision-making. By incorporating real-time image processing and deep learning models, the robot can be improved to identify crop diseases, nutrient deficiencies, and weed patterns with higher accuracy, allowing for more precise and adaptive field operations.

Another promising direction is the enhancement of the robot’s autonomy and connectivity through the use of Internet of Things (IoT) technologies. By connecting the system to cloud platforms, farmers can monitor and control operations remotely, access real-time data, and receive predictive insights for better farm management. The addition of advanced navigation systems, such as RTK-GPS, can further improve positioning accuracy, making the robot suitable for large-scale and highly precise agricultural applications.

Future improvements can also focus on energy efficiency and sustainability. The integration of solar panels and improved battery technologies can extend operational time and reduce dependence on external charging sources. Additionally, optimizing the mechanical design to handle diverse terrains and extreme weather conditions will increase the reliability and durability of the system in real-world environments.

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