



# BLUETOOTH CONTROLLED WIRELESS AGRICULTURE WEEDING ROBOT

**Mrs. Nivedita Dilipsingh<sup>1</sup>, M.Kavyanjali<sup>2</sup>, N,Sai Krishna Reddy<sup>3</sup>, R. Sathvik kumar<sup>4</sup>**

<sup>1</sup>Associate Professor of ECE Department <sup>2,3,4</sup>UG students of ECE department

<sup>1</sup>Dept. of Electronic and Communication Engineering

<sup>1</sup>TKR College of Engineering and Technology, Hyderabad, India

**ABSTRACT:-** Automated processes in the field of agriculture have become more and more reliable and efficient. There are many difficulties faced when manpower is used. It is time consuming and becomes tedious. Robotic systems integrated with various control methods can be very useful in doing repetitive work, such as seed sowing process where the same movement is continuous.

## I. INTRODUCTION

In olden days technology wasn't developed that much. So they were sowing, plowing and pesticide spraying by hands. But now a days technology is developed. So now it's not imperative to do seeding in sunlight. By using robot technology one can sit in a cold area and can do seeding by monitoring the robot motion. Today's agricultural field demands to find new ways of agricultural operation to improve performance efficiency. In the field of agriculture various problems are faced by the growers in the operation like seed sowing, plowing, and weeding. Also the equipment's utilized to perform the operations are very heavy. Due to migration of human's in the cities the labor problem occurs. Now a day's robotics technology plays a paramount role in all sectors. In other countries robots are operated to perform different operations in the agricultural field. We can make the use of accessible technologies and the robotics technology in the farming system to reduce the sweats of growers and also to reduce time, energy and needed cost.

Bluetooth controlled wireless agriculture weeding robot perform various tasks. They can be operated a controlled remotely by farmers through a mobile application. So the agricultural system in India should be advance to reduce the efforts of farmers. Various numbers of operations are performed in the agriculture field like seed sowing, weeding, pesticide spraying etc. Very basic and significant operation is seed sowing. But the present methods of seed sowing are problematic. The micro controller moves the vehicle motors in forward direction in case no obstacle is detected. If in case obstacle is detected by the sensor then the micro controller stops the device to avoid the any damage to humans/plants etc. The main intention of machine can also be used to reach the places where farmers make harder efforts for farming such hill areas, mountains etc. Where land is not plane. This is how we can use this robot in different fields. By forthcoming manipulation in programming, it can be reorganize consequently. Robotic agriculture the future of agricultural mechanization. Developed agriculture needs to find new ways to improve efficiency. One avenue is to utilize obtainable information technologies in the form of more intelligent machines to degrade and target energy inputs in more further ways than in the past.

## II. OBJECTIVES

- Automated process in the field of agriculture have become more and more reliable and efficient.
- There are many difficulties when man power is used.
- It is time consuming and becomes tedious.

- Robotic systems integrated with various control methods can be very useful in doing repetitive work, such as seed sowing process where the same movement is continuous.

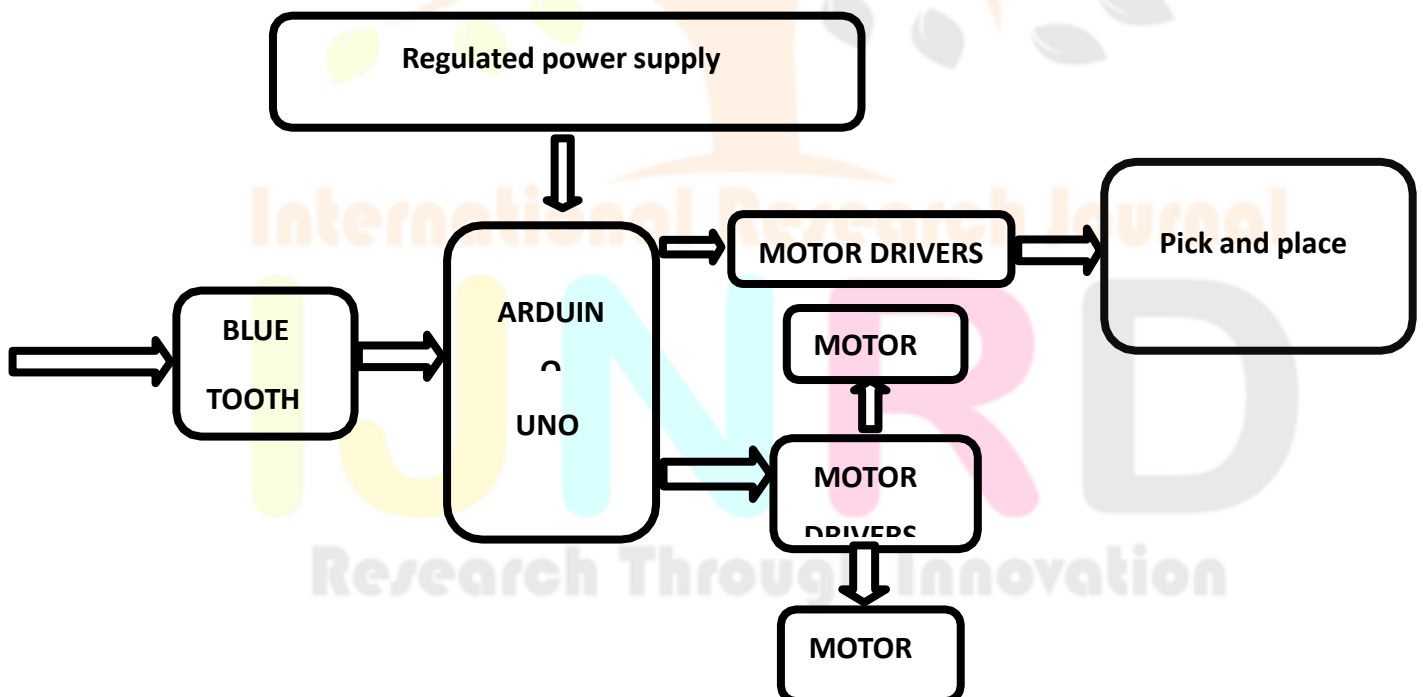
### III. EXISTING SYSTEM

Present now there are different types of agricultural robot where they perform the single task at a time only and they have low efficiency. There are different types of robot like Demeter robot, seed sowing robot, plough robot, fire fighting robot. Demeter robot is an speed rowing and is a capable of planning harvesting operations for an entire field machine. The robot is required more space and perform the only few tasks. Seed sowing robot is a device that helps in the sowing the seeds in the desired position. It assisting the farmers in saving time and money seed sowing is one of the main processes of farming activities. The seeds are dispelled on the seed beds in manually. It requires a substantial amount of mortal sweet and also time consuming and major. But major disadvantage is bulk and very hard to perform the task and understand the device operation. In present there are different types of robot's they only perform one or two task only.

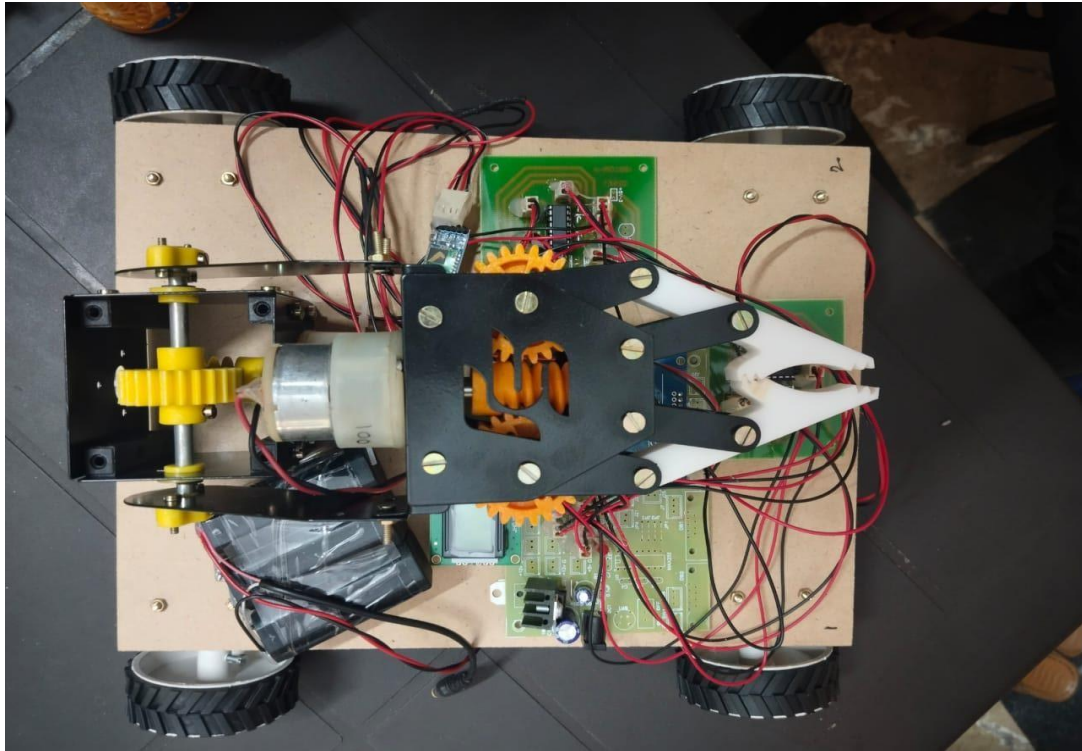
### IV. PROPOSED SYSTEM

This robot is use to perform the different types of operations where farmers can easy to perform and understand the device. Where existing system different robots are used to perform the only one task at a movement and it is very hard to understand the device. By this robot multiple operations are to be performed at wide range tasks to performed. Where farmers did not need any external sources to use the robot if in case field workers are not available then our robot will do the work in substitute of them. Here our robot will perform the task of four workers individually.

### V. BLOCK DIAGRAM



## VI.RESULT



## VII CONCLUSION

Coordinating elements of all the equipment parts utilized have been created in it. Presence of each and every module has been contemplated out and put cautiously, in this manner adding to the best working of the unit. Also, utilizing exceptionally progressed IC's with the assistance of developing innovation, the task has been effectively executed. Consequently the venture has been effectively planned and tried.

## VIII.FUTURE SCOPE

Our endeavors to foster a minimal expense coordinated framework for improvement of pick and place robot have up to this point brought about the iterative advancement of a tried, demonstrated equipment stage. The product stack has been created for restriction, route, and radioactive component identification. Future work should be possible on the heartiness of court limitation and further code enhancements, which are two important stages for the combination of these parts. The inevitable objective for this venture is completely mechanized bottle filling pick and spot robot with least space. The primer outcomes for limitation, movement arranging and jug recognition are empowering. The correspondence from the Robots to GUI application can be carried out through the base station so it have some control over up to 10 Robots from the GUI application through the base station that utilization a got remote channel utilizing encryption and decoding. Impressively bigger transmission capacity framework ought to be ready since video web-based feature is wanted. The future work can make the framework vigorous to ecological varieties; it can likewise plan to foster the dynamic usefulness of the stage to make a genuinely independent framework

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