



UNIVERSITY OF
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Performance Evaluation of Single-Shot Detection Models for Weed Identification on Open-Source Datasets

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Introduction: Hazards of Weed Plants



Weeds cause \$138 Billion annual loss in the USA ^[1]



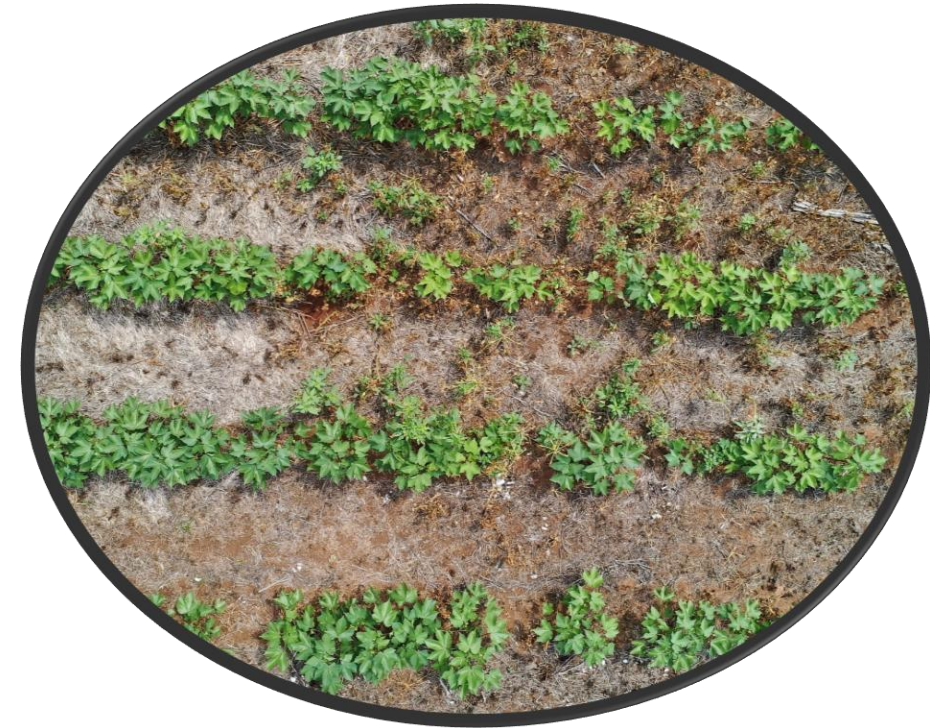
Weed management accounts for more than 30% of production costs in specialty crops ^[2]



Weeds degrade the quality of specialty crops by competing for essential nutrients



Critical to control weeds within the first 4-6 weeks of crop plantation ^[3]



Weeds in cotton field at J. Phil Campbell Sr.
UGA Research Center, Watkinsville, GA

Manual Weeding



Manual weed removal [8]

- **Time consuming**
- **Labor intensive**
- **Damaging to healthy vegetation**
- **Inefficient**

Herbicide Application



Chemical weed control [9]

- **Weed resistant plants**
- **In-organic**
- **Crop injury**
- **Negative impact on environment**

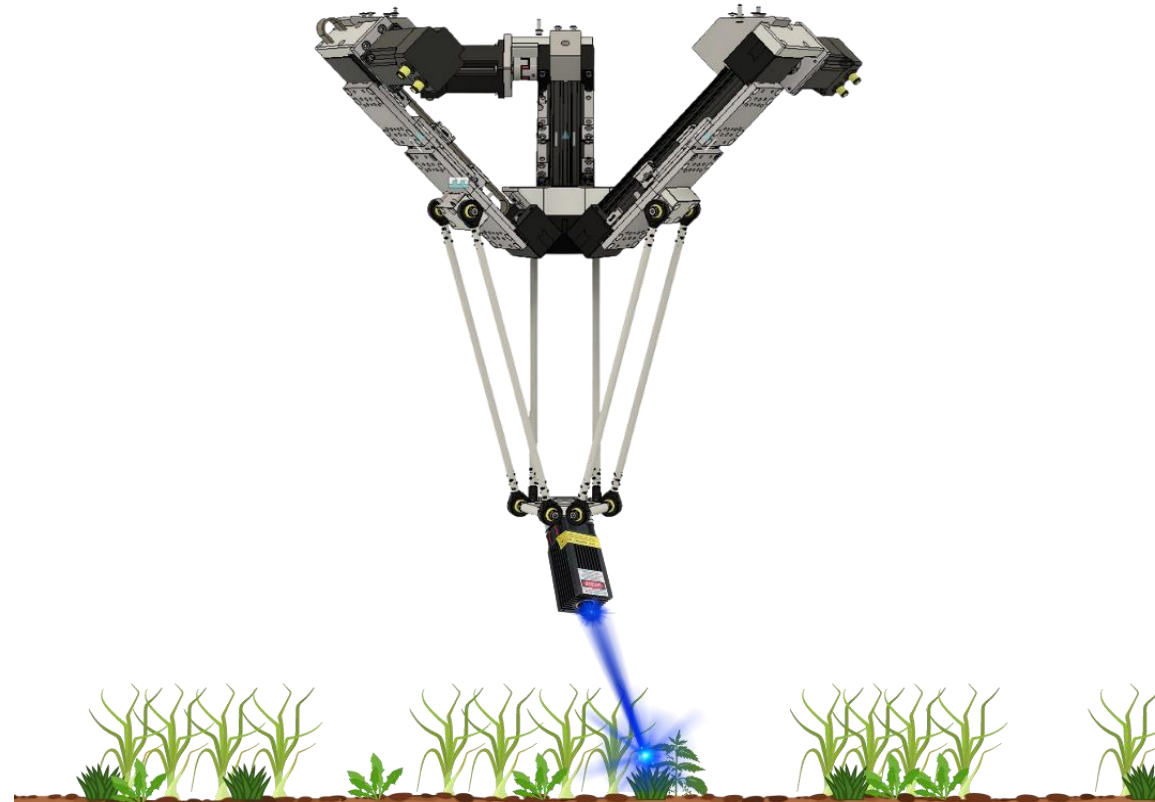
Robotic Laser Weeding

- 1 Organic process
- 2 Reduced risk of crop damage and increased weeding efficiency
- 3 Reduction in Soil Disturbance
- 4 Precise operation
- 5 Cost effective
- 6 Automation and labor savings



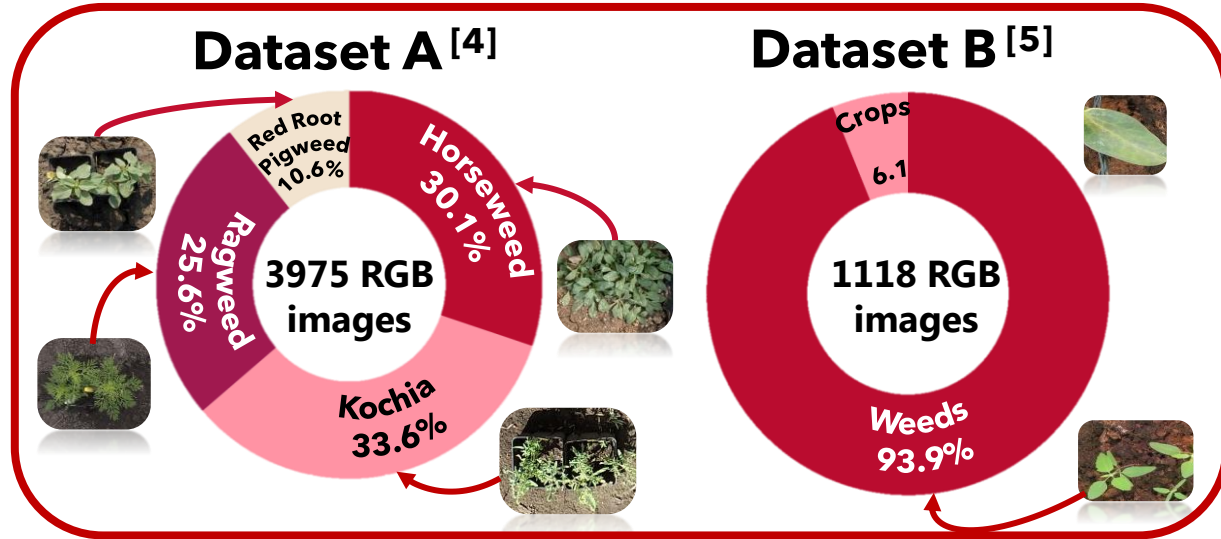
Goal and Objectives

Enhancing weed detection under variable lighting conditions using advanced deep learning models

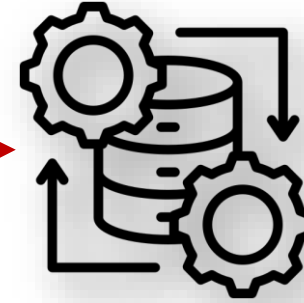


Methodology

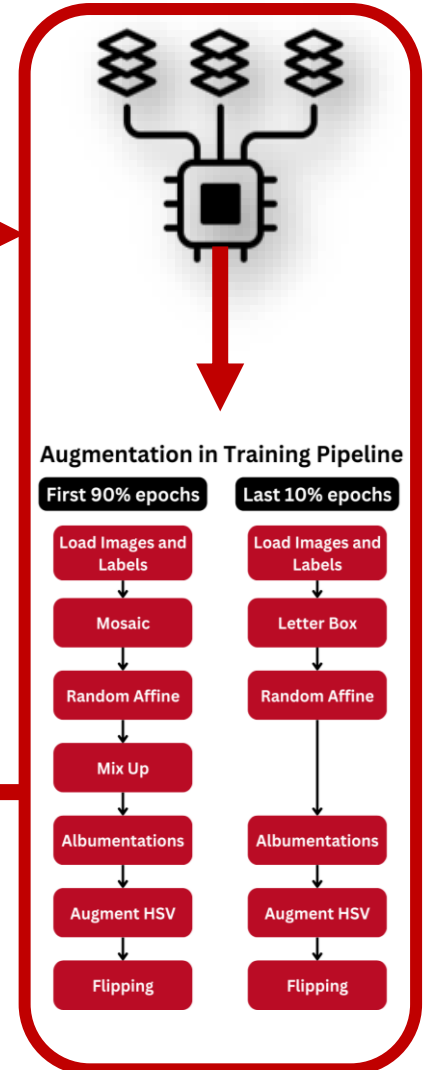
Data Acquisition



Pre-processing



Train YOLOv9, RT-DETR, YOLO-World and YOLOv8



Optimal Model Selection

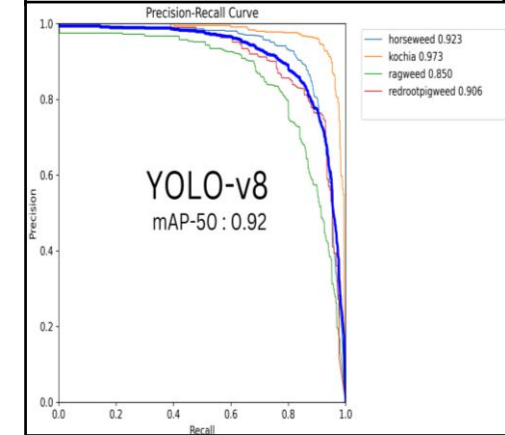
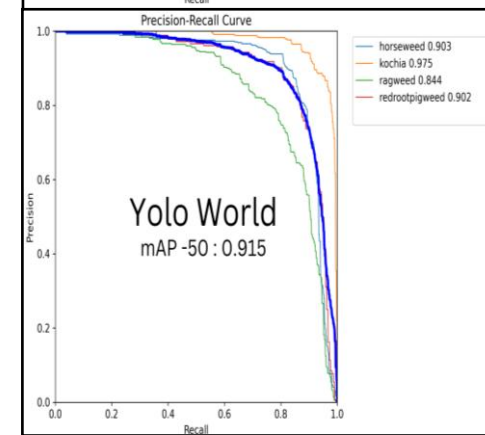
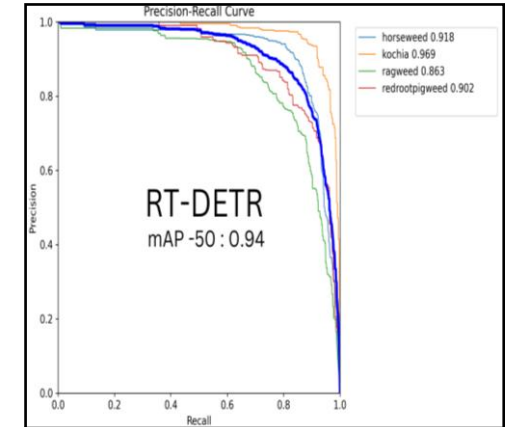
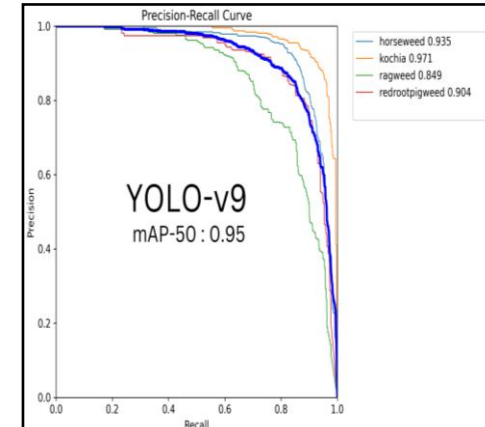
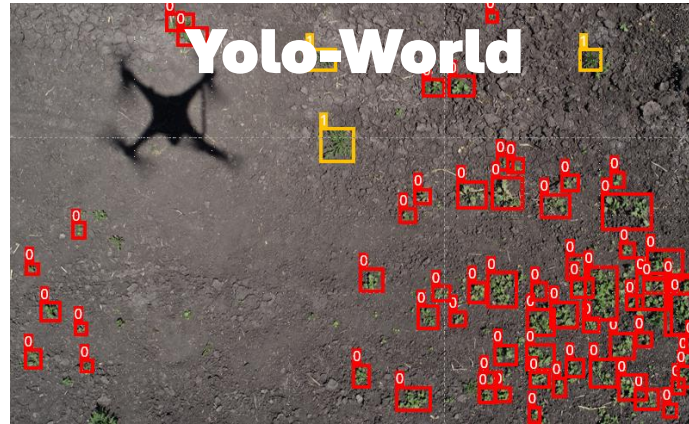
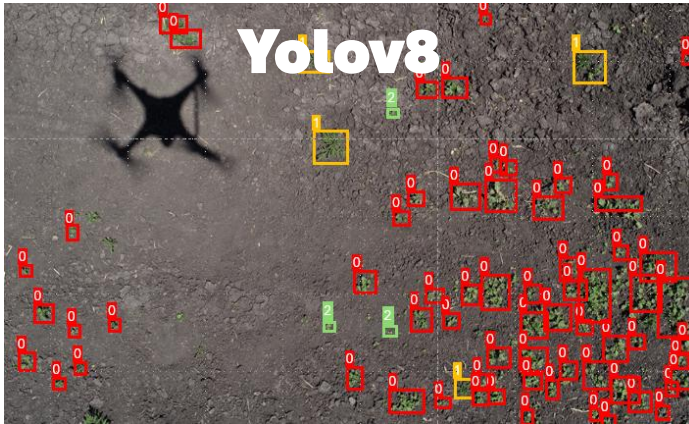
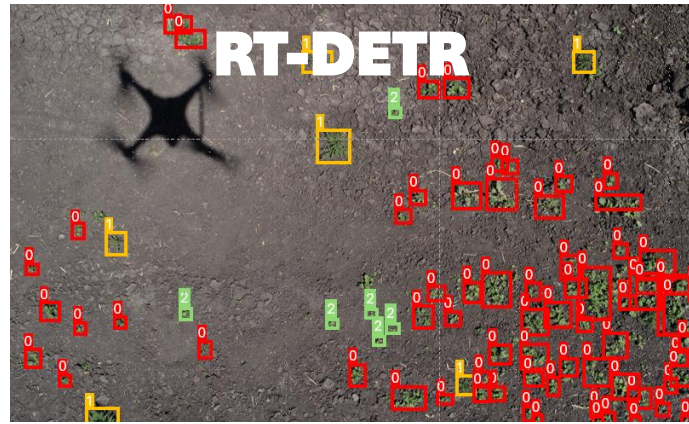
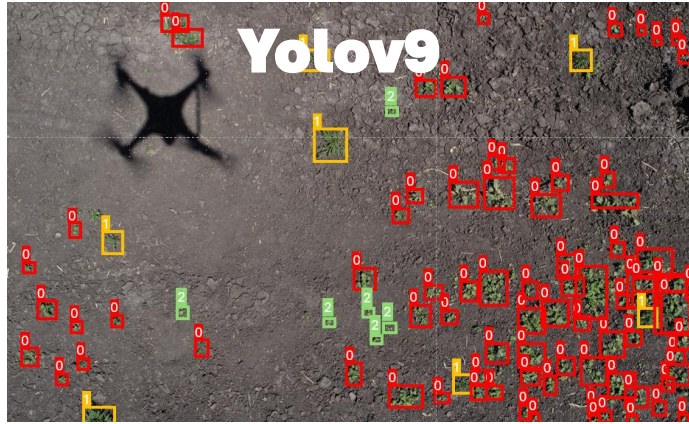


Performance Evaluation



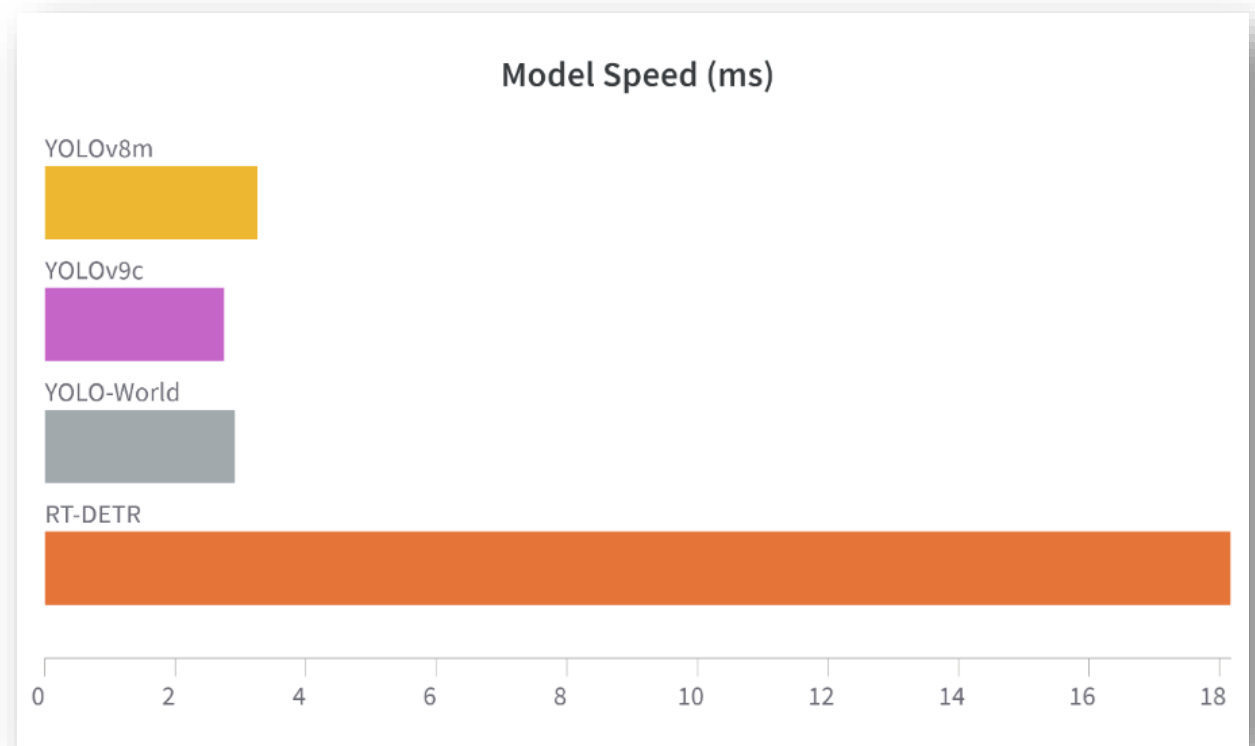
Inference Computation

Results

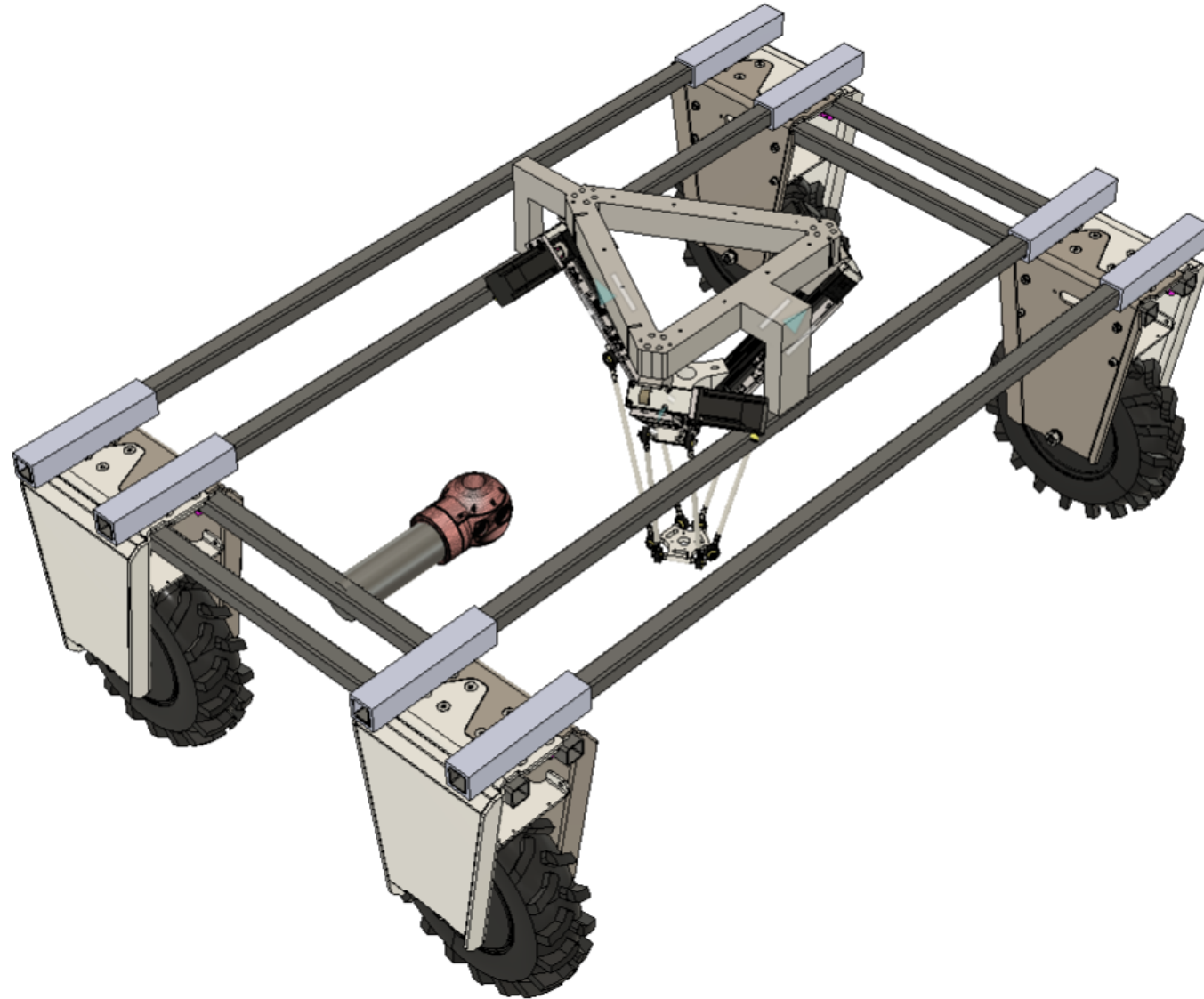


Conclusion

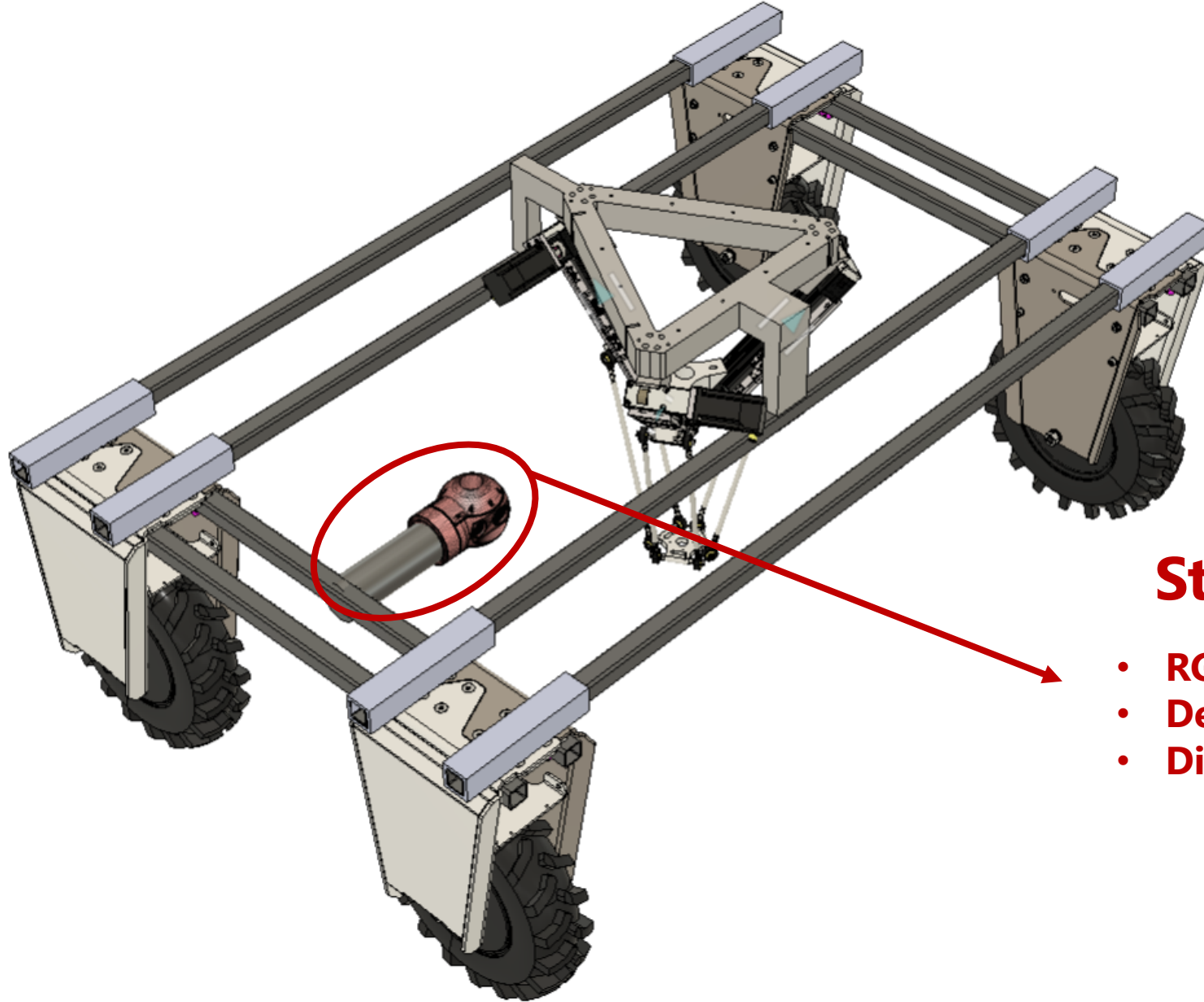
- YOLOv9 had the fastest inference speed at **2.9ms**, while RT-DETR, with similar results, was the slowest.
- YOLOv9 outperformed YOLOv8 with a **2.15%** improvement
- Real-time capabilities
- Suitable for robotic system integration



Future Work



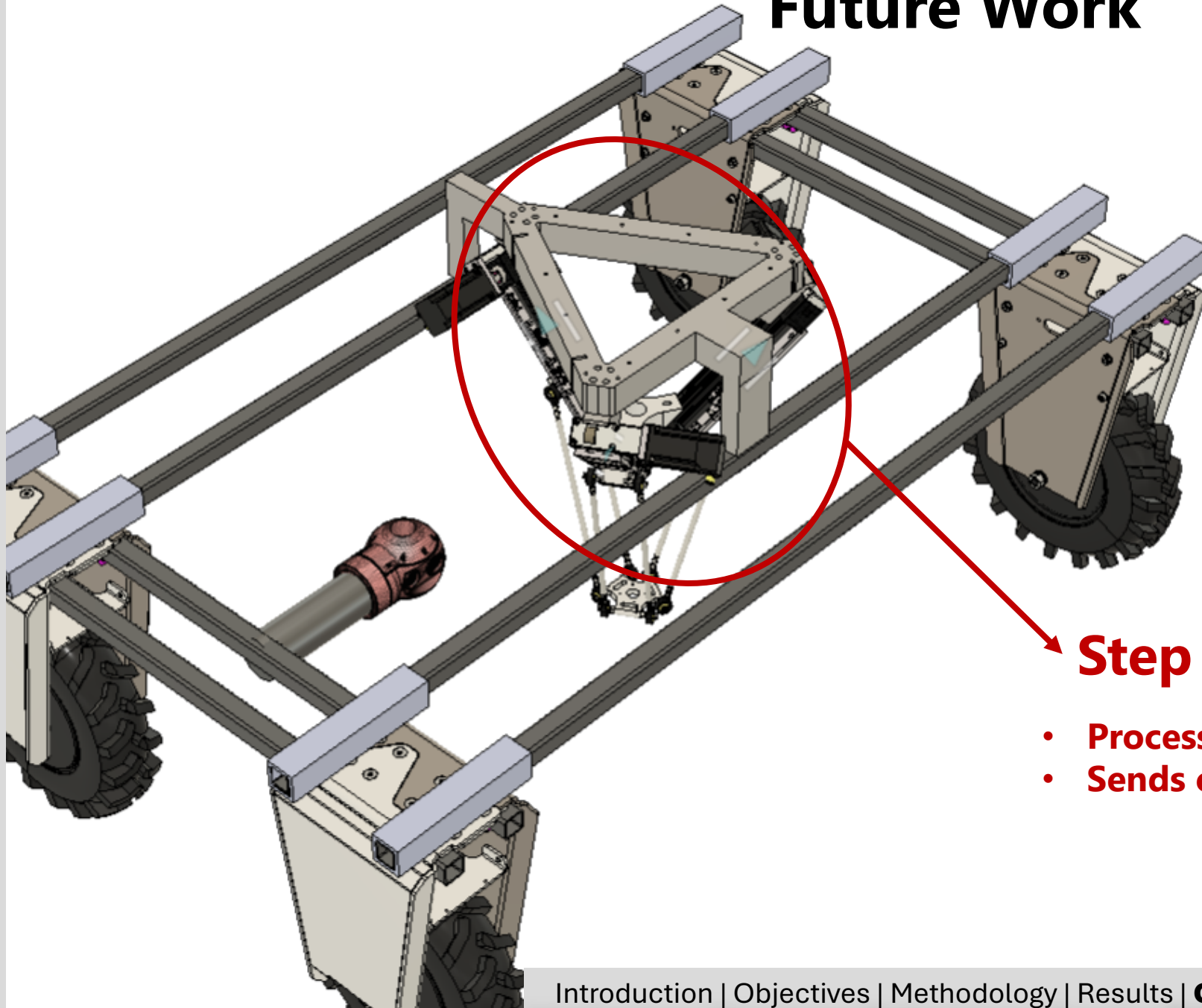
Future Work



Step 1

- RGB Camera and other sensors
- Detect multiple weed species
- Diverse field conditions

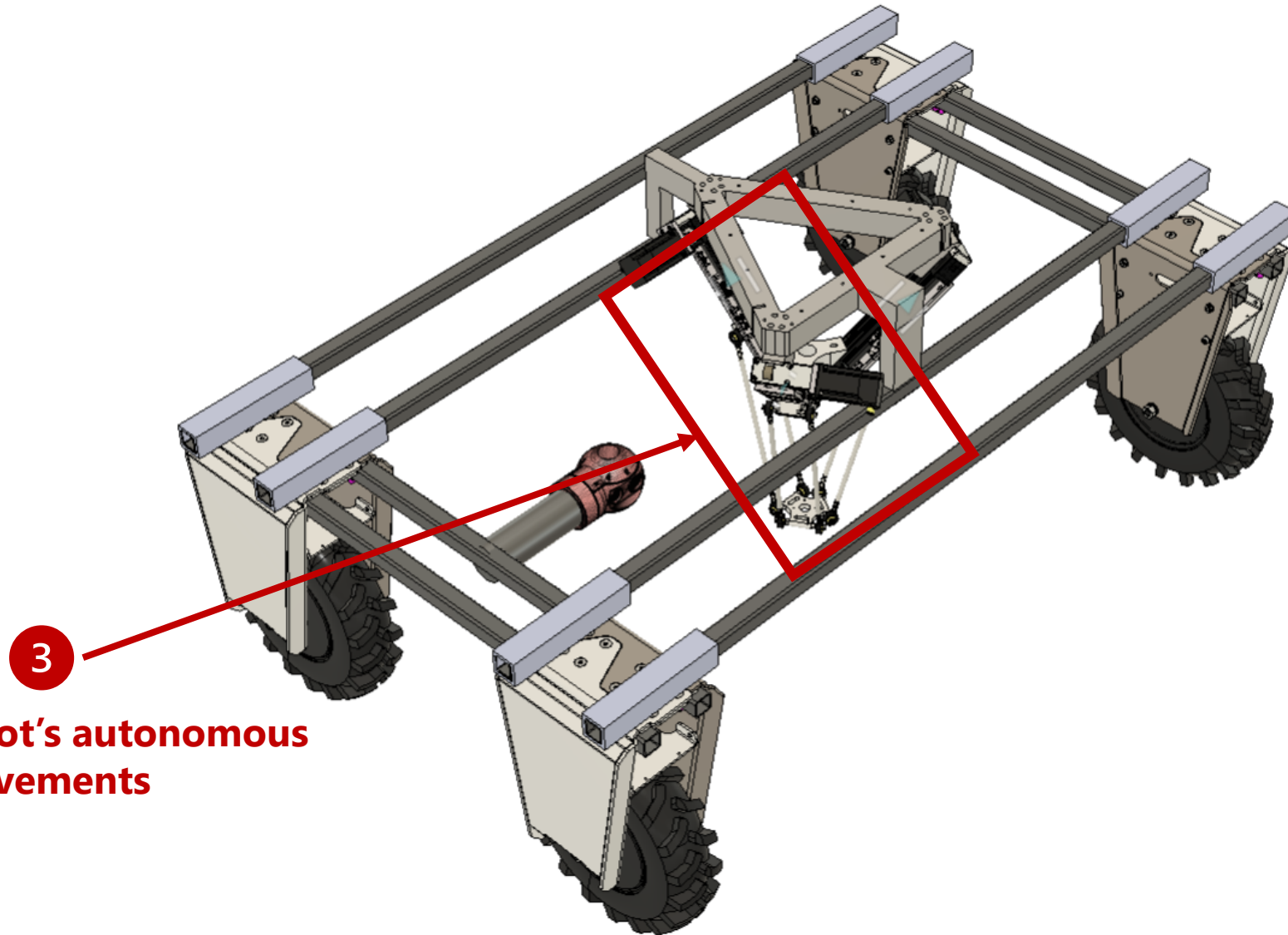
Future Work



Step 2

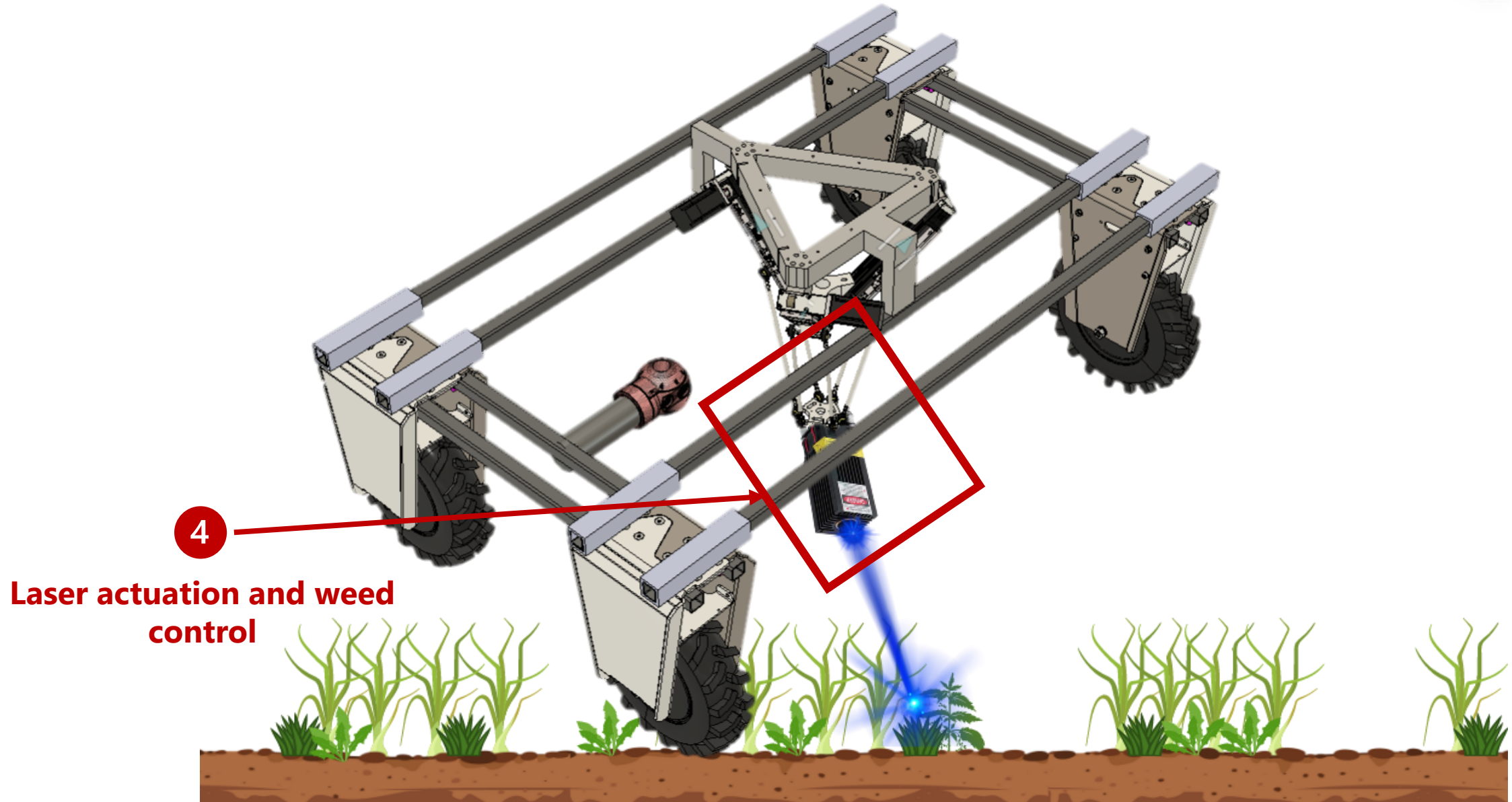
- Process input data
- Sends control signal

Future Direction



3
Execute robot's autonomous
movements

Future Direction



Acknowledgments



Institute for Integrative
Precision Agriculture
UNIVERSITY OF GEORGIA



GS24-316

Thank you!
Any Questions?

References

[1] <https://www.fs.usda.gov/detail/r8/landmanagement/resourcemanagement/?cid=fseprd972844#:~:text=Studies%20show%20that%20economic%20losses,by%20non%2Dnative%20invasive%20species>

[2] <https://wssa.net/2016/05/wssa-calculates-billions-in-potential-economic-losses-from-uncontrolled-weeds/>

[3] <https://crops.extension.iastate.edu/encyclopedia/managing-weeds-protect-crop-yields>

[4] Rai, N., Mahecha, M. V., Christensen, A., Quanbeck, J., Zhang, Y., Howatt, K., . . . Sun, X. (2023). Multi-format open-source weed image dataset for real-time weed identification in precision agriculture. *Data in Brief*, 51, 109691.

doi:<https://doi.org/10.1016/j.dib.2023.109691>

[5] Sudars, K., Jasko, J., Namatevs, I., Ozola, L., & Badaukis, N. (2020). Dataset of annotated food crops and weed images for robotic computer vision control. *Data in Brief*, 31, 105833. doi:<https://doi.org/10.1016/j.dib.2020.105833>