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An UGV-based Precision Spraying System for Chemical Apple Blossom Thinning on Trellis Trained Canopies

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INTRODUCTION



- ❖ More than 19,500 acres of apples are planted in Pennsylvania by about 2,400 farmers (USDA NASS, 2019).
- Apple blossom thinning plays an important role to ensure the quantity and quality of the crop production.
- ❖ Precision apple blossom thinning remains as a challenge: inadequate thinning / excessive thinning.



INTRODUCTION

- Precision apple blossom thinning
- Automatically detect flower clusters and spraying chemical thinner onto targets

BUT

- Need human labor to drive around orchard
- Extremely slow due to the speed of linear actuator



Cartesian target spraying system developed in 2022



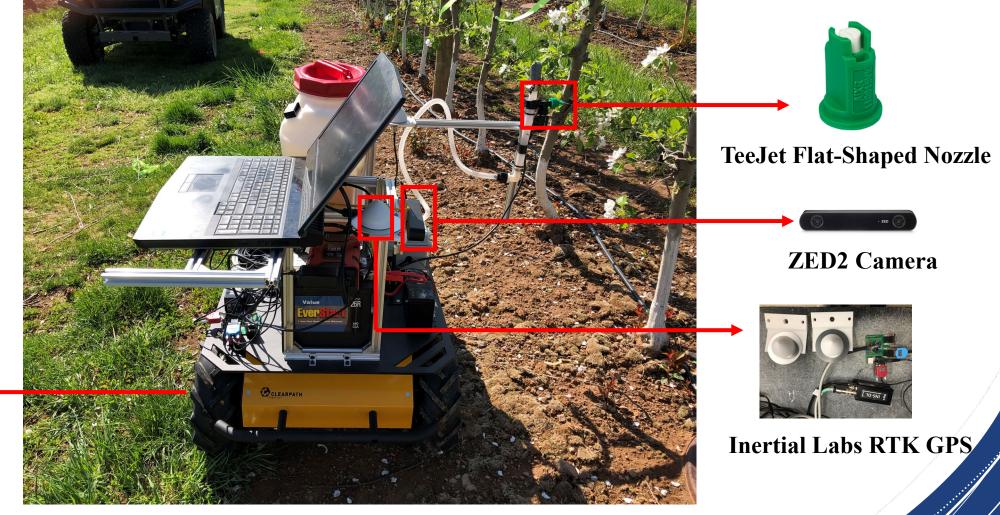
GOAL & OBJECTIVES

Goal: Develop an autonomous robotic system that can perform chemical thinning process for the apple canopies to reduce labor cost and minimize the chemical thinner usage.

***Objectives:**

- Develop a machine vision system that automatically detects and locates the position of thinning targets (apple flower clusters).
- Transform pixel coordinates into geographic coordinates for the communication between vision system and RTK GPS.
- Evaluate the performance of the overall system and compare with other spraying techniques.





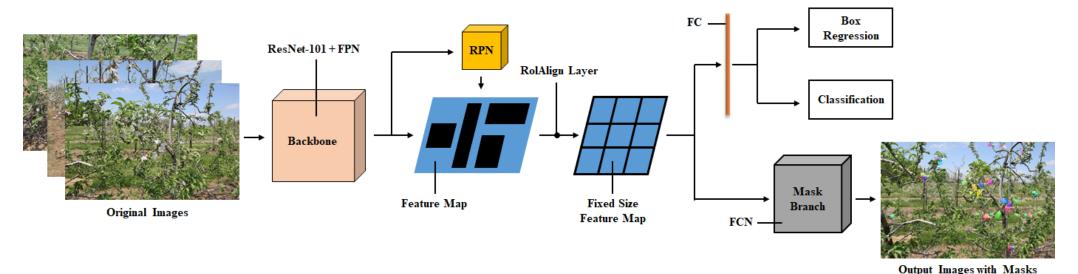


Husky A200



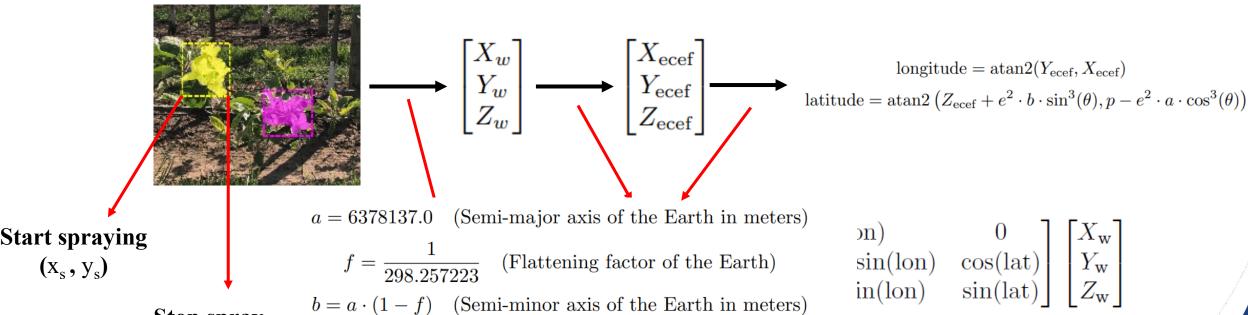
❖ Mask R-CNN Based Instance Segmentation

- Transfer learning: COCO dataset
- Training-testing split ratio: 2000:400 (5:1)
- Loss function converged after 100,000 iterations





Object Localization and Georeferencing



Start spraying (x_s, y_s)

> **Stop spray** (x_e, y_e)

$$f = \frac{1}{298.257223}$$
 (Flattening factor of the Earth)

 $b = a \cdot (1 - f)$ (Semi-minor axis of the Earth in meters)

$$e = \sqrt{2f - f^2}$$
 (Eccentricity of the Earth)

$$p = \sqrt{X_{\text{ecef}}^2 + Y_{\text{ecef}}^2}$$
 (Distance from the Z-axis in meters)

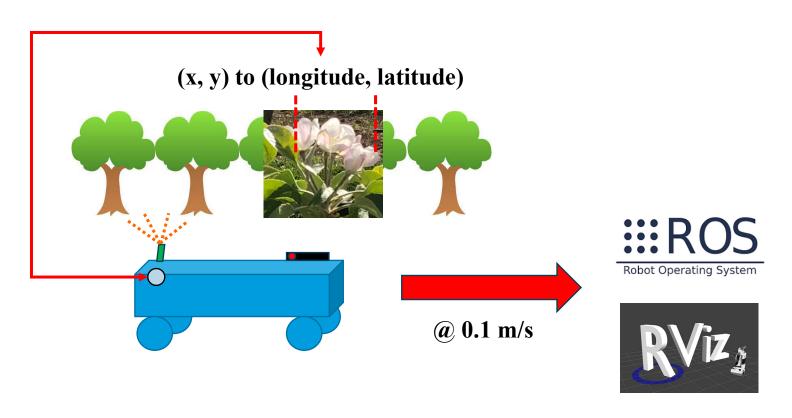
 $\theta = \operatorname{atan2} (Z_{\text{ecef}} \cdot a, p \cdot b)$ (Angle between Z-axis and XY-plane)

ECEF coordinates to geographic coordinates

PennState

F coordinates

Overview of the UGV-based Spraying System

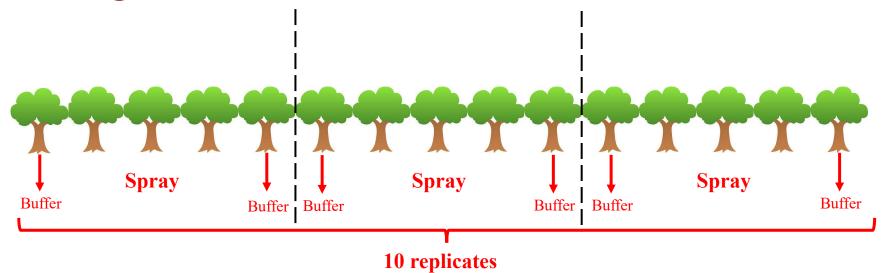




Experimental Design



UGV-based sprayer





Air-blast sprayer

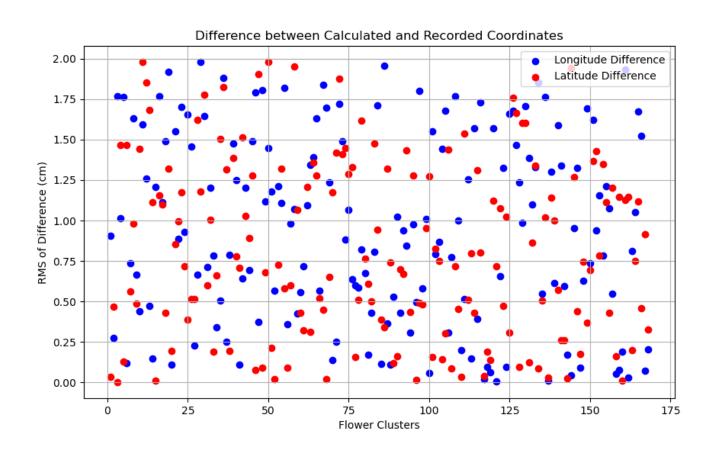


30 consecutive trees



RESULTS

❖Georeferencing Accuracy Assessment



- Ground truth coordinates measured manually using GPS.
- Compare with geographic coordinates computed by vision system.
- RMSE lies within ± 2 centimeters.



RESULTS

Spraying Coverage Test with Blue Indicator







RESULTS

UGV-based Sprayer vs. Air-blast Sprayer vs. Cartesian Sprayer

- UGV-based spraying system took longer time than air-blast sprayer.
- The usage of chemical thinner (Lime Sulfur + Oil) decreased greatly in target spraying.
- Least green fruit set indicates that the UGV-based spraying system obtains the best thinning process.

Spraying System	Average Spray Time per Tree (s) (s)	Chemical Usage (gal) (gal)	Green Fruit Set per Cluster
UGV-based Sprayer	10.2	2.2	2.3
Air-blast Sprayer	2.4	4.6	2.6
Cartesian Sprayer	18.6	2.3	2.4



CONCLUSION

- A novel approach for apple blossom thinning was developed using the UGV-based spraying system.
- The machine vision system correctly detect the target flower clusters and output the location in the format of geographic coordinates with RMSE less than 2cm.
- Comparing to other thinning techniques, the UGV-based spraying system decreases the usage of chemical thinner by 60% and improves the effectiveness of thinning.



THANK YOU

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