Journal
of the
Oriental Institute
M.S. University of Baroda
ISSN: 0030-5324

FERTILIZERS SPRAY DRONE IN AGRICULTURE

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Abstract- Use of fertilizers/pesticides in agricultural fields is necessary for better crop yields. The main disadvantage of manual spraying is that it can causefew health issues like respiratory ailments, cardiac diseases etc.,[1-2] to the human who is spraying these fertilizers. Sometimes, dermal exposure happens when your skin is exposed to pesticides. This can cause irritation or burns. In order to avoid this risk and spray the fertilizers/pesticides uniformly, we came up with the idea of automatic fertilizer/pesticide sprayer using a drone. It is also known as UAV i.e. Unmanned Aerial Vehicle. More recently quadcopter[7] designs become popular in unmanned aerial vehicle (UAV) research. These vehicles use an electronic control system and electronic sensors which stabilizethe aircraft. The Sprayer movement is controlled by DC motor at low velocity, up & down direction according to the plant height. It can also cover larger areas of fields while spraying fertilizers/pesticides in a short span of time when compared to a manual sprayer. The proposed system can be remotely operated through any electronic device like mobile, laptop etc.

Indexed Terms- UAV, Agricultural Drone, ArduPilot, Automatic Spraying.

I INTRODUCTION

About 70-80% of India's population either directly or indirectly depends upon the farming and agriculture.

But most of the farming techniques used by Indianfarmers are traditional. Farmers who perform manual labour in areas treated where they can face major exposure to pesticides from a direct spray, by contact with pesticide residues on the crop or soil or droplet drift from the neighbouring fields .This kind of indirect exposure is Use of UAVs can help in reducing these deaths and other health problems. An unmanned aerial vehicle (UAV)[5] has a wide range of applications in fields of agriculture, forestry etc. for observing, transporting loads and sensing. UAVs are operated remotely either by telemetry or other protocols, where the operator maintains visual contact with the aircraft along pre-determined paths using GPS and other guiding sensors like compass. A commercial UAV[5] was used to spray crops and the work rate and spray deposition measured for a number of spray techniquesand spray volume application rates..

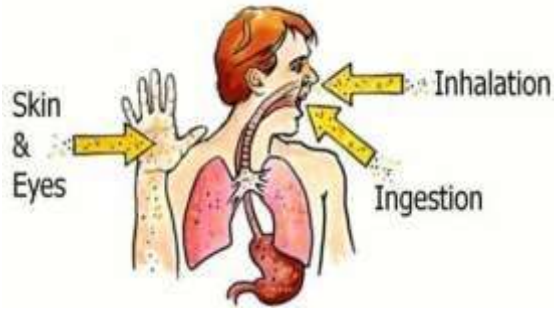

Fig: Possible ways for pesticides to enter the body

II LITERATURE REVIEW

Dongyan et al. (2015) [1] experimented on effective swath width and uniformity of droplet distribution over aerial spraying systems like M-18B and Thrush 510G.These agricultural planes flew at height of 5 m and 4 m respectively and with this experiment they reach to conclusion that flight height leads to the difference in swath width for M-18B & Thrush 510G. Huang et al. (2015) [2] made a low volume sprayer which is integrated into unmanned helicopters. The components which are used in our system are described in detail with their working and operation as follows

The helicopter has a main rotor diameter of 3 m and a maximum payload of 22.7 kg. It used to require at least one gallon of gas for every 45 minutes. This study paved the way in developing UAV[3] aerial application systems for crop production with higher target rate and larger VMD droplet size. The WHO (World Health Organization) estimates there are more than 1 million pesticide cases in every year. In that more than one lakh deaths in each year, especially in developing countries due to the pesticides sprayed by human being and handling of pesticides. The health effects of pesticides include asthma, allergies and hypersensitivity, and pesticide exposure to cancer, hormone disruption and problems with reproduction and fetal development. Other pesticides may be irritated the skin and eyes. More pesticides are very dangerous carcinogens. Other pesticides may be 9 International Academic Research Journal of Engineering Sciences February affects the hormone and endocrine system of the body. Even though very low levels of exposure during spraying may have leads to health effects. Pesticide exposure can cause a wide range of neurological health effects in body such as memory loss, loss of coordination, reduced speed of response to stimuli, reduced visual ability, altered or uncontrollable mood and general behavior, and reduced motor skills. Pesticide exposure can cause a range of neurological health effects such as memory loss, loss of coordination, reduced speed of response to stimuli, reduced visual ability, altered or uncontrollable mood and general behavior, and reduced motor skills.

III EXISTING SYSTEM

The following are few mostly used strategies for spraying pesticides and fertilizers.

1. Back pain sprayer:

This consists of a tank, a pump, a lance (for single nozzles) or boom (for multiple nozzles). The tanks contain a mixture of water (or another liquid chemicalcarrier, such as fertilizer) and chemical which will be sprayed in the form of droplets.

The man spraying fertilizers by using back pack sprayer it may leads to the health issues for the farmers heavily due to lifting more weight on their back side of their body.

Fig: Man spraying fertilizers using a backpacksprayer

2. Motor cycle driven multipurpose farming device:

In 1994, Mansukhbhai Ambabhai Jagani,developed an attachment for a motorbike to get a multipurpose tool bar. It addresses the twin problems of farmers .

Fig: Farmer using Bullet Santi to spray fertilizers inthe field

IV PROPOSED METHOD AND WORKING

We chose to automate UAV[5] instead of operating it manually, because this can save time and field monitoring can also become easy. For this purpose, we picked 913 MHz telemetry as 433MHz is not an accepted range in India for making commercial purpose drones. By utilizing a progression of various separation measure/imaging hardware like Pi Camera, drones can record the plant condition while spraying which will be useful in identifying the crop diseases and plant monitoring.

Instruments like sensors that utilize ultrasonic resounding enables drone to identify the crop location so that fertilizers are sprayed correctly on the target amid flight. Since this is a pilot project and a prototype, it is presently attainable for automatons to fly at sufficiently low heights to splash pesticides and target specific segments of a field to appropriate it in likely mannerThe brushless motors are normally 3 phases. Therefore, direct supply of DC power will not turn the motors on. That is why the Electronic Speed Controllers (ESC) comes into picture. The ESC generates three high frequency signals which have different but controllable phases. They continually generate frequencies to keep the motor turning.

We made use of a dedicated micro controller called ArduPilot[8] for automation of drone which is designed specifically for unmanned aerial vehicle applications. This micro controller is programmed with the help of development software called Mission Planner which can run on either on Windows or Linux. To automate this we can either use a computer with Mission Planner software or a smartphone with Mission Maker application as a ground base station. These applications can help us directing the drone by uploading the way points through which it has to travel before taking of the vehicle.

Initially open the mission planner application and connect to the quadcopter[7] via telemetry. Once you are connected to the quadcopter, we set the waypoints by clicking on new mission option. After way points are selected, the designed mission should be uploaded to the micro controller. The micro controller processes the information and waits for the command to run the mission.

Then the APM 2.8 subtracts the current location (taken from the GPS) from the waypoint which given in the mission. According to the result, the quadcopter[7] moves in desired direction with the help of Electronic Speed Control (ESC), Global Positioning System (GPS) and Compass. Every motor carries ¼ of the weight of Quadcopter. Hencebuilding a quadcopter with live control as well as autopilot capabilities that is versatile enough requires tackling several problems. Using Raspberry Pi, we are going to record the crops while spraying to check whether the targeted crops receive the required amount of fertilizers. We have used the motor as brushless motor, because they can achieve high torque. The aircraft must have an adequate payload capability as well as stabilization and localization capability.

The movement of the quadcopter is controlled via 4 motors. The motor on the backward should rotate in a higher RPM than the front motors so that the quadcopter can move in forward direction. This way the movement of the quadcopter is controlled. In case if the quadcopter loses its connection with the ground station, we can operate the drone manually using the receiver.

Fig Image of proposed drone model

On each of the brushless motor is mounted with a propeller. The 4 propellers are actually not identical in rotation. The motor torque and the law of physics will make the Quadcopter[7] spin around itself if all the propellers were rotating the same way, without any chance of stabilizing it. The larger diameter and pitchthe more thrustthe propeller can generate. Here we are using 10*4.5” propellers.

Components Used:

1.Brushless Motor:

Brushless Motors are similar to normal DC motors. These brushless motors have three coils on the inner of the motor, which is fixed to the mounting. These motors are called as brushless motors because the brush which takes care of switching the power direction in the coils is absent.

ESC (Electronic Speed Control):

The brushless motors are normally 3 phases. Therefore, direct supply of DC power will not turn the motors on. That is why the Electronic Speed Controllers (ESC) comes into picture. The ESC generates three high frequency signals which have different but controllable phases. They continually generate frequencies to keep the motor turning.

3. Propellers: On each of the brushless motor is mounted with a propeller The 4 propellers are actually not identical in rotation. The motor torque and the law of physics will make the Quadcopter spin around itself if all the propellers were rotating the same way, without any chance of stabilizing it. The larger diameter and pitch the more thrust the propeller can generate. Here we are using 10*4.5" propellers.

4 Battery:

This complete automated unmanned aerial vehicleruns on a battery. It is recommended to use a LiPo (Lithium Polymer) battery because of less weight. Here we are going to use a 11.2V, 5200mAh LiPo battery.

5. GPS (Global Positioning System):

We are using Global Positioning System device, so that the quadcopter can navigate from one position to other. This is also used in automation purpose also. With the help of GPS, we create the waypoint to fly the quadcopter autonomously.Here we are using UBLOX 7M GPS with in-built compass. This is can take up to seven points for flying.

6.ArduPilot:

This ardupilot is a microcontroller specially designed and developed for building autonomous vehicles. light movement is controlled by using the mission planner software on a laptop or mission maker application via smartphone.

7.2.4 GHz RC Transmitter and Receiver:

We are using a 2.4GHz range Radio Controller Transmitter and Receiver, so that if the quadcopter loses its connection with the base control, we can gaincontrol over it using this remote control and operate it.

light movement is controlled by using the mission planner software on a laptop or mission maker application via smartphone. It also includes the accelerometer, gyro meter and an in-built compass. Microcontroller is the brain of the quadcopter[7] as it is responsible for all actions it performs, from take-off and landing to autonomous flight of quadcopter.

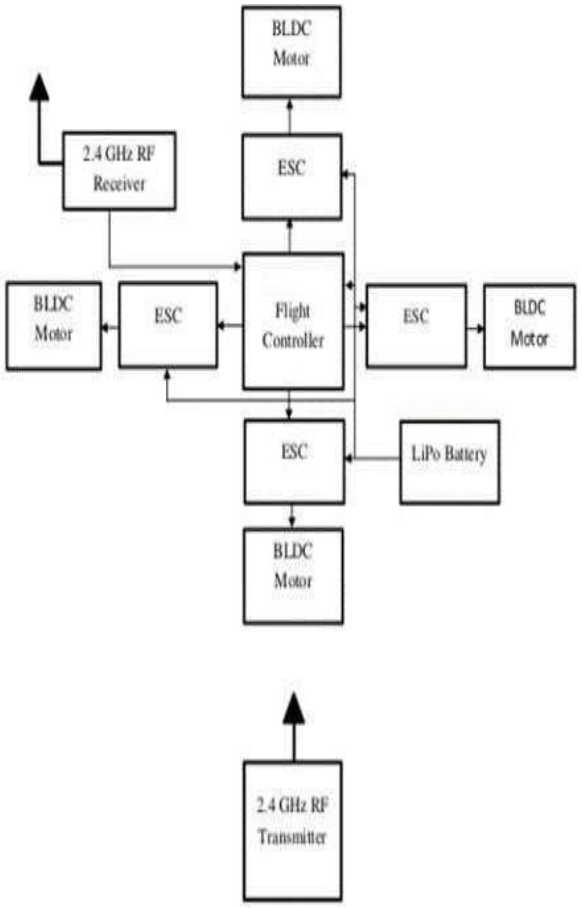

Fig: Drone architecture

V Results and conclusions

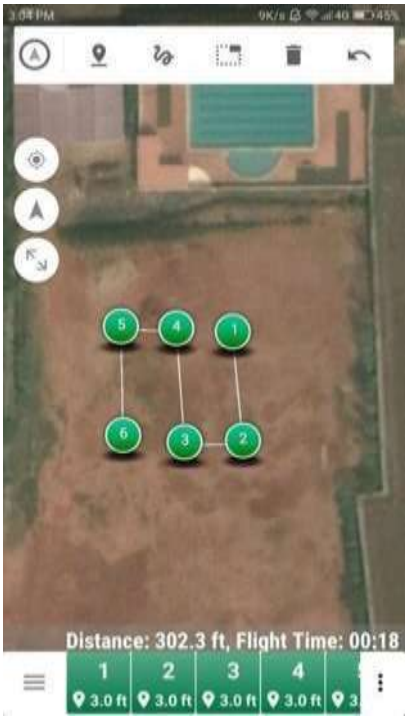

Fig 1: Creating waypoints on mission maker application

Fig 2: Take off point of drone (point 1)

Fig 3: Final point of path (point 6)

The vehicle started from point 1 as shown in the map and traversed the path and reached the point 6. After reaching the point 6, it again changed its direction and returned to the home point which is point 1. It is to be noted that this prototype should not begiven altitude input above 4 ft. giving which can lose the contact with the ground station.

CONCLUSION

We can further extend this project by implementing tree surveillance by using image processing techniques like histogram matching algorithms, clustering methods to discover the rate of ripeness (evolution) of fruits, crop aging could be checked. With the assistance of few parameters like shape of the fruit, colour-shade of fruit skin, we can achieve the above goals. This helps agriculturists by decreasing their manual work, by saving time, resources and money.. After a real world model is built and distributed throughout country with a subsidy, the Indian agriculture will be revolutionized and drastic improvement in the agriculture sector as well as in the health conditions ofthe farmers can be seen.

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