



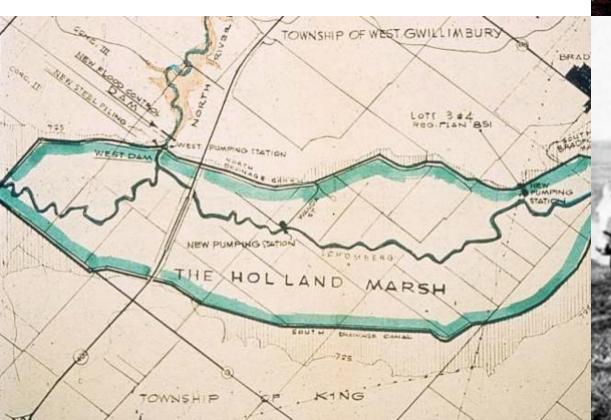
# Adaptation of AgRobotics for Root and Bulb Vegetable Production in High Organic Matter Soils





# **The Holland Marsh**

- 50-80% organic matter
- Drainage began in the 1920s
- 7000 acres of muck soil















## **Robot Trials - 2022**

### Nexus Robotics – La Chèvre

- Mechanical weeder
- Scouting capabilities



### Naïo – Dino

- Autonomous tool-carrying robot
- Focused on weeding



# **Robot Trials - 2023**

### Naïo – Orio

- Autonomous tool-carrying robot
- On-board RTK GPS
- Fully electric, lithium batteries
- Four-wheel drive
- 5.5km/h top speed
- 1450kg weight
- Very adaptable























Stopped

kpl

-10

HF:



Tille



















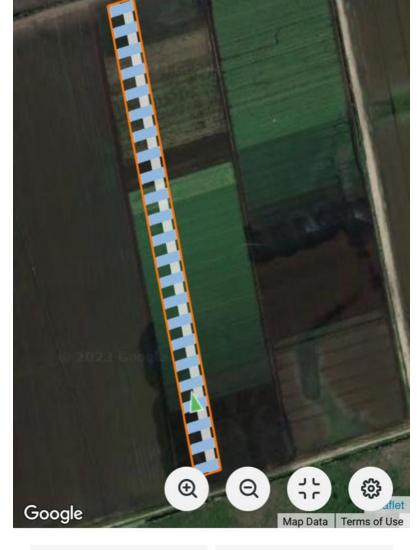
# **Robot Trials - 2023**

## FarmDroid – FD20

- Seeding and weeding robot
- Geotags each seed
- Inter- and intra-row weeding
- 0.95km/h top speed
- Solar-powered
- 1050kg weight







Live mode **Off** 



Droid is On





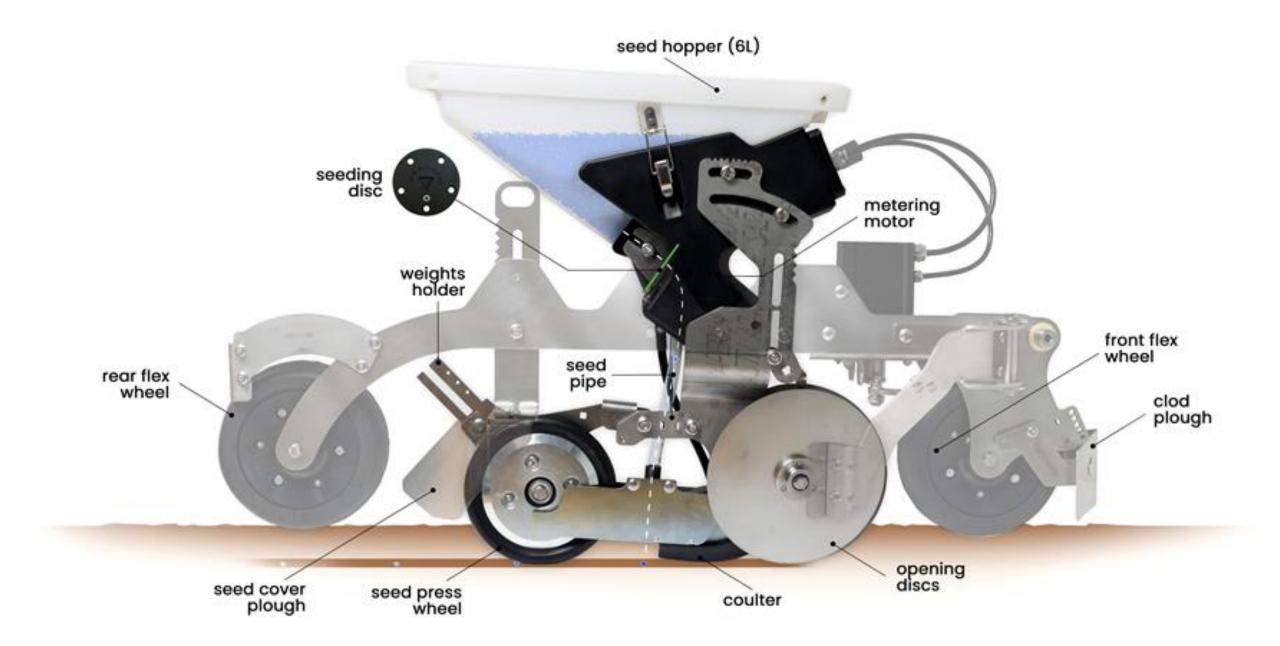


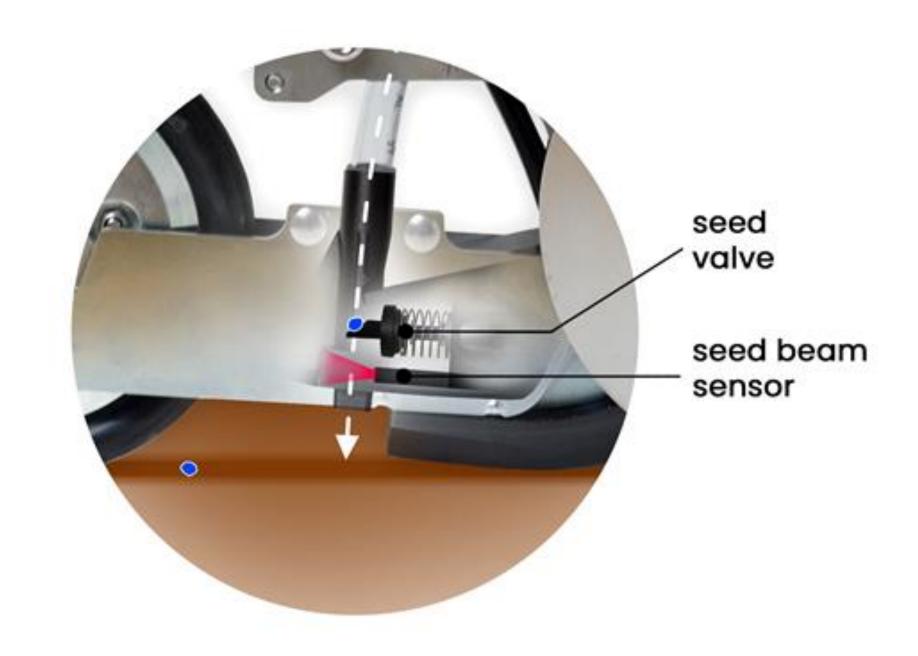












## **Single Row FD20**

• 3.4 cm between seeds





# **Seeding Methods**

#### **Conventional**

- 5 cm between seeds
- Double row

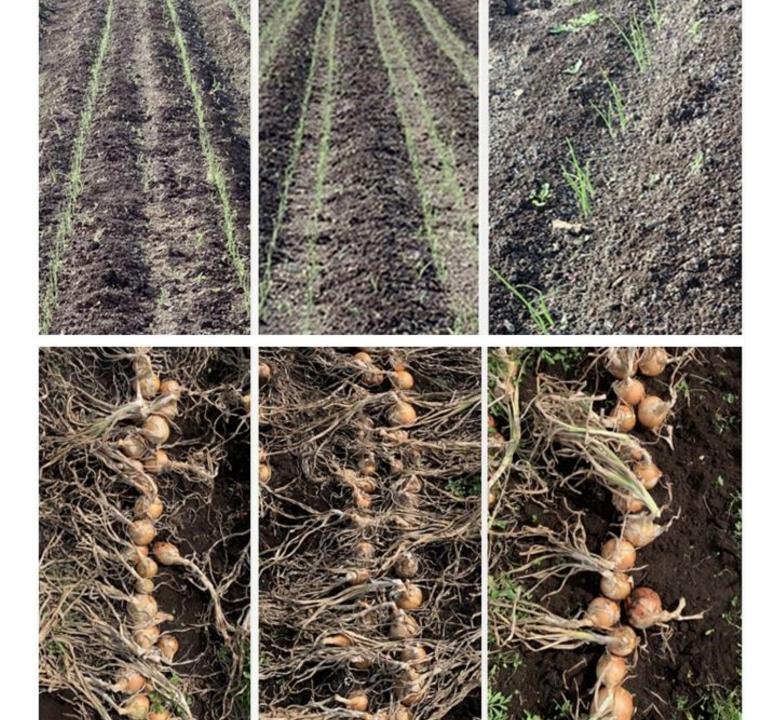


### **Triple Cluster FD20**

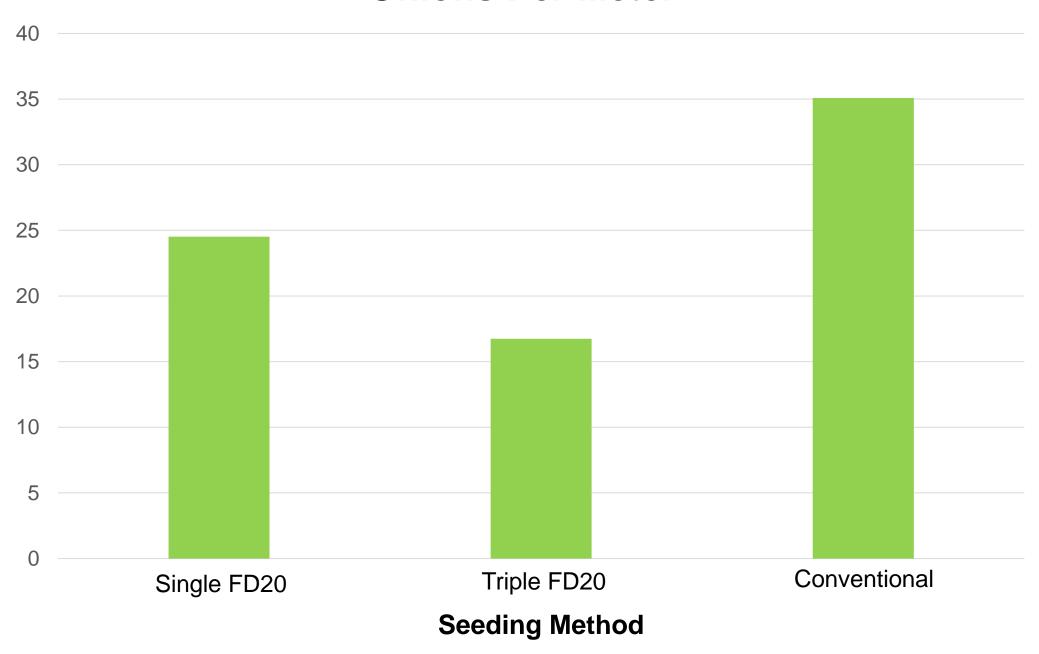
• 12 cm between clusters



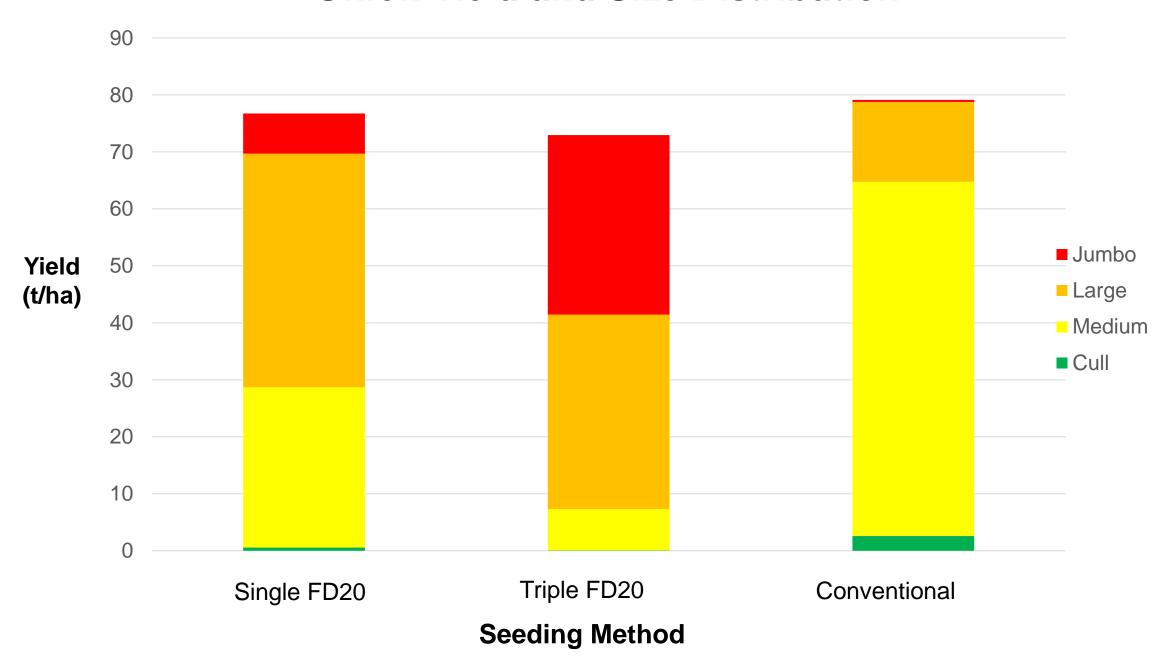




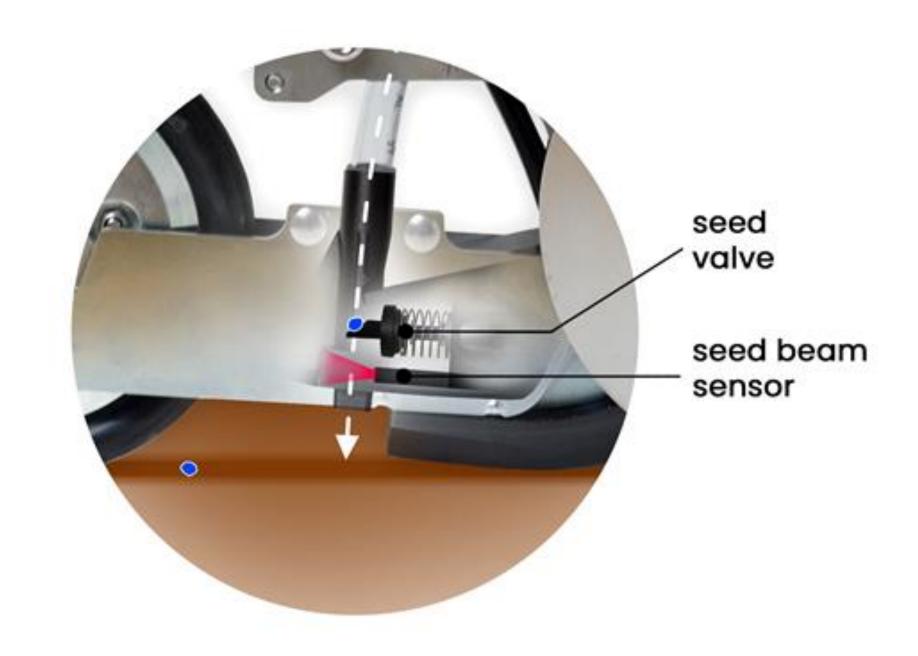
## **Onions Per Meter**



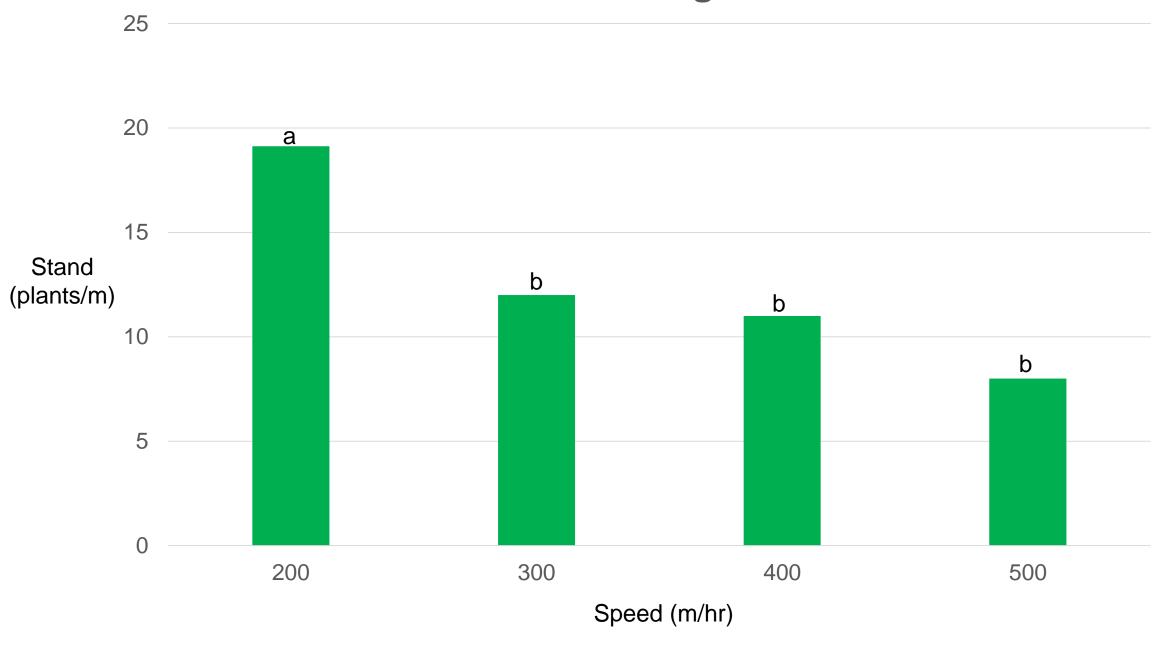
## **Onion Yield and Size Distribution**







# **Onion Emergence**











## **Future Work**

#### FarmDroid – FD20

- 4 wheels instead of 3
- Improve tooling for weeding
- Optimize seeding methods



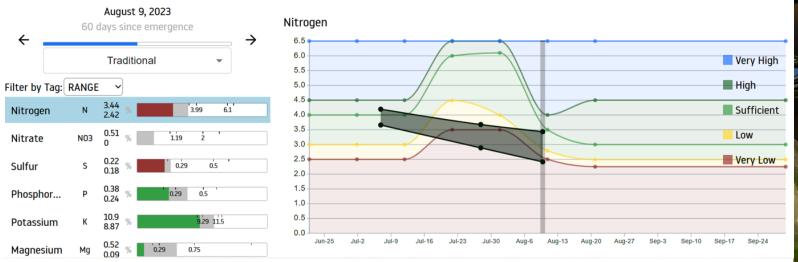
#### Naïo – Orio

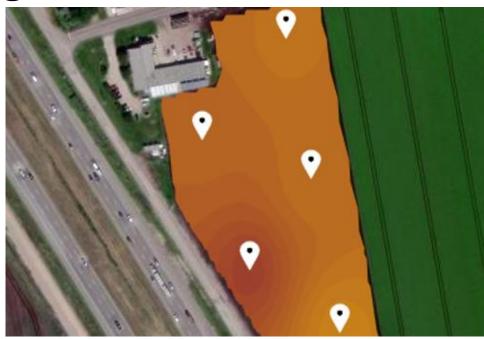
- Compare against tractor
- Figure out seeding implement
- Work in onions and other crops



## **Picketa - LENS**

- LENS Leaf Evaluated Nutrient System
- Estimates nutrient content for 13 macro and micronutrients
- Model is currently being built for onions
- Could be mounted to a robot in the future







# Acknowledgements

 Thank you to Haggerty AgRobotics, OMAFRA, Picketa, the Ontario Agri-Food Innovation Alliance, the AgRobotics Working Group, and cooperating growers



