**Developing Machine Vision System for Robotic Elderberry Harvest**

**Gian Lucca Teixeira1, Dr. Jianfeng Zhou2**

1Undergraduate Student, Department of Electrical Engineering and Computer Science, University of Missouri, Columbia, MO, 65201 Email: gat7hb@umsystem.edu

2Assistant Professor, Plant Science and Technology, College of Agriculture, Food and Natural Resources, University of Missouri, MO, 65201 Email: zhoujianf@missouri.edu

**Abstract:**

The market and demand for American elderberries are increasing dramatically in recent years. This growth, however, is being restrained by the inefficient current solution of manual labor harvesting. Our goal is to develop a robotic harvesting solution that will be selective and efficient in the harvesting process. In this project, we focused on developing a machine vision system based on a depth camera and artificial intelligence. The function of the machine vision system is expected to detect, classify, and localize ripped elderberry clusters, and send this information to the actuation of robotic arms. In this preliminary study, the depth camera was used to manually collect imagery data in both laboratory and field conditions. A total of 2000 images were collected at 3 varieties, fields, and growth stages. Meanwhile, color stand for ripeness color reference was used in 100 images where the maturity level was manually accessed, and 15 manual 3D coordinate measurements were collected at the field plus 216 measurements collected in the lab. To recognize fruit clusters, we chose the state-of-the-art YOLOv7 deep learning model due to its record speed and accuracy in object detection. Randomly selected images were labeled using labelImg software. All the labeled images were divided into 70:10:20 for training, testing, and validation respectively. Results showed that, with just 104 labeled images used for training, validation, and testing, returned a mean average precision metric (mAP) of 84% and object validation loss of 2.7%. These results showcase the high possibility and great potential for developing a robust robotic harvester for elderberry. We will continue our work by finishing the design of the camera system, testing classification models to accurately judge cluster ripeness levels, and extracting the 3D coordinates of the detected clusters.