AGROVISION: CROP MANAGEMENT COMPANION

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Dissertation submitted in partial fulfillment of the requirements for the degree of

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STUDENT DECLARATION

We hereby declare that the project report titled AGROVISION: CROP MANAGEMENT COMPANION submitted by us to Department of Information Technology, Padre Conceicao College of Engineering, Verna in partial fulfillment of the requirement for the award of the degree of Bachelor of Engineering in Information Technology under Goa University is a record of bona fide project work carried out by us during the period from 2024 to 2025 under the guidance of Dr. Razia Sardinha.

We further declare that the work reported in this project has not been submitted and will not be submitted, either in part or in full, for the award of any other degree or diploma in this institute or any other institute or university.

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ABSTRACT

This research presents a practical and efficient approach to addressing key challenges in modern agriculture through the integration of machine learning and geospatial technologies. The proposed system enables real-time crop monitoring, early disease detection, and targeted weed management using advanced computer vision techniques. At the core of the system lies YOLO NAS (You Only Look Once – Neural Architecture Search), a high-performance object detection model renowned for its speed and accuracy in real-time applications.

The model is trained on a combination of publicly available datasets from platforms such as Kaggle and data collected from real-world farm environments, ensuring robustness and adaptability to various agricultural scenarios. The system provides three essential capabilities: identifying crop ripeness to assist in timely harvesting, detecting early signs of plant diseases for prompt treatment recommendations, and distinguishing between crops and weeds to support selective weed removal while preserving crop integrity.

Geographic Information System (GIS) software is employed to spatially map the detected plant health data, allowing farmers to localize and address specific areas that require attention. The integration of GIS with machine learning enables precise, location-specific decision-making, improving farm resource management and operational efficiency.

This research specifically focuses on strawberry plants, implementing the system on a mobile rover platform equipped with a camera for video capture and wireless communication. The rover is remotely controlled via the Blynk IoT platform, making the solution accessible and user-friendly. Designed as a cost-effective and scalable solution, this work offers an economical and practical method for small- to medium-scale strawberry farming applications.

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CONTENTS

LIST OF FIGURES

LIST OF TABLES

LIST OF ABBREVIATIONS

AI	Artificial Intelligence
ML	Machine Learning
IoT	Internet of Things
GIS	Geographic Information System
GPS	Global Positioning System
YOLO	You Only Look Once
NAS	Neural Architecture Search
CNN	Convolutional Neural Network
RGB	Red Green Blue (color model)
DC	Direct Current
ESP8266	Espressif Systems Protocol 8266 (Microcontroller)
GUI	Graphical User Interface
QGIS	Quantum Geographic Information System
ASFF	Adaptive Spatial Feature Fusion
HRS	Hybrid Receptive Structure
MBM	Multi-Branch Module
FPS	Frames Per Second

CHAPTER 1

INTRODUCTION

1.1 INTRODUCTION AND BACKGROUND OF PROJECT

Agriculture, the backbone of the global food supply, is increasingly challenged by rising labor costs, unpredictable weather patterns, pest and disease outbreaks, and the need to produce more with fewer resources. Traditional farming practices, which often rely on manual labor and periodic inspections, are no longer sufficient to meet the demands of modern agriculture. As a result, farmers and researchers worldwide are turning to smart farming technologies to bridge this gap and ensure sustainable food production for future generations.

In this context, machine learning (ML) and computer vision have emerged as transformative tools. By enabling machines to mimic human visual perception and make sense of complex field conditions, these technologies support timely interventions that can prevent significant crop losses. When combined with Geographic Information Systems (GIS), they provide not only detection but also spatial awareness — allowing farmers to pinpoint exactly where issues occur and respond efficiently.

The AGROVISION project exemplifies this synergy. It integrates advanced object detection, real-time autonomous data collection, and intuitive geospatial mapping into a single, farmer-friendly platform. This system addresses three critical pain points in crop management:

- Identifying fruit ripeness to ensure harvesting occurs at the optimal time for maximum market value and quality.

- Detecting early signs of plant diseases to facilitate prompt treatment and prevent spread.

- Recognizing weeds accurately to enable selective removal, thereby reducing chemical use and preserving soil health.

Initially focused on strawberry crops, AGROVISION demonstrates how even labor-intensive, high-value crops can benefit from smart monitoring. Strawberries are particularly prone to rapid spoilage if not harvested at the right stage and are vulnerable to diseases that can wipe out yields within days. This makes them an ideal candidate for showcasing the practical benefits of integrated ML and GIS technologies.

The hardware backbone of the project is a lightweight, mobile rover equipped with an ESP8266 microcontroller and a camera capable of capturing continuous video streams while navigating crop rows. Farmers can operate this rover remotely using the Blynk IoT platform, which provides an intuitive interface for live monitoring and control. Captured images are processed using the YOLO NAS algorithm, a cutting-edge deep learning model that delivers high detection accuracy with low latency, making it suitable for real-time field conditions.

Detection results are processed and visualized in QGIS, which maps the exact locations of ripe fruits, diseased plants, and weeds. This geospatial intelligence empowers farmers to take precise actions, whether it is to harvest at the right moment, apply localized fungicides, or remove weeds selectively. By integrating these elements, AGROVISION demonstrates a scalable approach to bridging the digital divide in agriculture and ensuring that modern technology is accessible to farms of all sizes.

1.1.1 SIGNIFICANCE OF AUTOMATION IN AGRICULTURE

One of the defining characteristics of modern agriculture is its drive toward sustainability. Sustainable farming practices emphasize not only increasing productivity but also conserving natural resources, maintaining soil health, and ensuring economic viability for farmers. Automating monitoring tasks aligns perfectly with these goals by enabling precise, site-specific actions instead of broad, generalized treatments.

Furthermore, automation addresses the issue of seasonal labor dependency. Many farms, especially those cultivating delicate fruits like strawberries, require significant manual labor during harvest seasons. However, recruiting and retaining workers is increasingly difficult and expensive. Autonomous monitoring systems like AGROVISION reduce the reliance on human scouting, allowing limited labor resources to focus on tasks that still demand manual skills, such as selective hand-picking.

The significance also extends to improved traceability and compliance. Modern consumers demand transparency about how their food is grown and handled. Automated systems record consistent, objective data about field conditions and crop health, providing verifiable records for food safety certifications and organic labeling. This added layer of traceability can open up premium markets for farmers.

Additionally, automation serves as a valuable educational tool. Smallholder farmers, often unfamiliar with advanced technologies, can gain confidence through user-friendly, semi-autonomous systems that gradually introduce them to data-driven farming. Over time, this fosters digital literacy and encourages broader adoption of smart agriculture solutions, contributing to national and global agricultural modernization efforts.

1.2 MOTIVATION FOR RESEARCH

The motivation for this research stems from the reality that while advanced technologies for agriculture exist, they often remain out of reach for small and medium-scale farmers due to high costs, technical complexity, and lack of local adaptation. In developing nations, where agriculture supports a large portion of the economy, these barriers hinder technological adoption and limit productivity gains. There is an urgent need for systems that are not only technically sound but also practical, affordable, and user-friendly for everyday farm use.

Moreover, strawberries are a high-value horticultural crop that requires intensive care and timely management. Issues like fungal infections, nutrient imbalances, and pest attacks can drastically reduce quality and yield if not identified promptly. Manual monitoring is both laborious and error-prone, particularly during peak growing seasons. By automating ripeness detection and disease monitoring, this research aims to reduce post-harvest losses and ensure that farmers can deliver consistent quality to markets, thus securing better income and market competitiveness.

Another key motivation lies in the gap between research prototypes and field-ready systems. Many academic projects achieve high accuracy under controlled conditions but fail when deployed in dynamic farm environments where lighting, weather, and plant variations pose additional challenges. This project is motivated by the goal of bridging this research-practice divide by creating a fully integrated, robust solution that can operate reliably in real-world conditions and adapt to various farm layouts and environmental factors.

Lastly, the motivation aligns with global goals for sustainable agriculture and climate resilience. By enabling precise and minimal use of agrochemicals and reducing unnecessary manual interventions, AGROVISION contributes to environmentally responsible farming. This resonates with international sustainability frameworks, such as the UN's Sustainable Development Goals (SDGs), particularly Goal 2 (Zero Hunger) and Goal 12 (Responsible Consumption and Production).

1.1.2 RESEARCH GAP

While many computer vision studies show promising detection results in controlled environments, there is a significant gap when it comes to deploying these models in unpredictable, real-world farm settings. Variations in sunlight, overlapping plants, motion blur, and background noise can drastically reduce detection accuracy if models are not adapted and tested for such conditions.

Another underexplored area is the fusion of detection results with geospatial intelligence. While GIS is widely used in large-scale precision agriculture, its integration with low-cost, real-time detection systems for small farms is rare. Bridging this gap can turn raw detection data into meaningful, location-specific insights, enhancing its utility for farmers.

Additionally, existing commercial solutions tend to be proprietary and closed-source, which limits customization and adds to the cost. There is a gap in the development of open, modular systems that researchers and local communities can adapt for different crops and regions. AGROVISION addresses this by leveraging open-source platforms like QGIS and Blynk, keeping the barrier to entry low.

Furthermore, few studies examine the human factor—how farmers interact with the system and interpret the data. This project incorporates user-centric design principles, ensuring that the output is presented in an intuitive, easily understandable format. This consideration is crucial for ensuring real-world adoption, especially in regions with limited technical expertise.

1.3 RESEARCH QUESTIONS,PROBLEM STATEMENTS &OBJECTIVES

This study is guided by the following research questions:

1. How can cutting-edge object detection models like YOLO NAS be adapted for robust, real-time detection of strawberry ripeness, diseases, and weeds under diverse farm conditions?

2. What is the optimal design for a cost-effective, IoT-enabled mobile rover that can autonomously navigate crop rows and capture high-quality field imagery?

3. How can detection results be translated into actionable, spatially-mapped information using open-source GIS tools to aid farmers in localized decision-making?

4. How effective is the integrated system when tested on real strawberry fields in terms of accuracy, speed, and user-friendliness?

Problem Statement: Traditional monitoring methods are laborious and inconsistent, and while standalone AI models exist, their lack of integration with real-time field data and spatial visualization limits practical utility. Farmers often lack timely, precise, and easily interpretable information to guide harvesting, disease control, and weed management.

Research Objectives:

- Develop and train a YOLO NAS-based object detection model for multi-class detection (ripe fruits, diseases, weeds).

- Design and implement a lightweight, remotely controlled rover with an ESP8266 microcontroller and camera for continuous image capture.

- Integrate machine learning outputs with GIS to produce clear, geospatial maps of crop health and maturity levels.

- Validate system performance under practical field conditions, addressing real-world challenges like lighting variability and occlusions.

- Demonstrate scalability and provide recommendations for extending the system to other crops and larger farm plots.

1.1.3 EXPECTED CONTRIBUTIONS

The expected contributions of this research are both theoretical and practical. On the theoretical side, it advances the understanding of deploying state-of-the-art object detection models in complex agricultural environments, highlighting challenges and proposing solutions for on-field accuracy and speed. It also contributes to methodologies for fusing vision-based detection with geospatial mapping in a lightweight, modular system.

Practically, this work provides a validated, replicable prototype that farmers can adapt to monitor strawberries or other crops. The low-cost hardware design and reliance on widely available components make it feasible for small-scale farmers to adopt without large capital investment. The user-friendly rover control and intuitive GIS output further enhance usability.

Moreover, the research offers a template for community-driven agricultural technology. By using open platforms and detailing the development process, it encourages local adaptation and customization, empowering communities to tackle their unique agricultural challenges without dependency on expensive, proprietary solutions.

Finally, the work opens avenues for future enhancements such as integrating additional sensors (temperature, humidity, soil moisture) or combining ground data with aerial imagery from drones. This multi-source data fusion could provide even deeper insights, moving towards fully autonomous, intelligent farm management systems.

1.4 REPORT ORGANISATION

This report is systematically organized to ensure clarity and a logical flow of ideas from concept to implementation and validation.

Chapter 1 provides a comprehensive introduction, detailing the project background, significance, motivation, research gaps, core questions, objectives, and expected contributions. It lays the groundwork for understanding the necessity and relevance of AGROVISION.

Chapter 2 delivers an in-depth literature review. It surveys key advancements in smart agriculture, reviews state-of-the-art object detection models, explores the evolution of autonomous ground vehicles for field data collection, and discusses the role of GIS in modern farm management. By identifying existing strengths and limitations, this chapter positions the present research within the broader academic and practical context.

Chapter 3 outlines the methodology. It explains the hardware design of the mobile rover, the configuration and training of the YOLO NAS model, the datasets used, and the integration approach for real-time detection and GIS visualization. It also describes the experimental setup for validating the system in actual strawberry fields.

Chapter 4 focuses on the implementation and system development. It details the step-by-step assembly and calibration of the rover, the deployment of machine learning algorithms on the microcontroller, the setup of the Blynk IoT platform for remote control, and the process for rendering detection results in QGIS.

Chapter 5 presents the experimental results and evaluation. It analyzes the detection performance in terms of accuracy, speed, and robustness under varying conditions. It also discusses practical challenges encountered, lessons learned, and the effectiveness of the GIS mapping in supporting decision-making.

Chapter 6 concludes the study. It summarizes key findings, discusses the implications for farmers and the agricultural sector, and highlights how the system addresses the initial research questions and objectives. The chapter ends with recommendations for future research, including scaling up the system, adding new features, and exploring broader applications in diverse agricultural settings.

CHAPTER 2

LITERATURE REVIEW

2.1 INTRODUCTION

Recent advancements in computer vision and deep learning techniques have significantly transformed modern agricultural practices, particularly in the domain of precision farming. Object detection models, especially the YOLO (You Only Look Once) family, have demonstrated exceptional capabilities in real-time monitoring and decision support for farmers. These models have been widely adopted for various tasks such as fruit ripeness detection, weed identification, and disease phenotyping, enabling the development of intelligent systems that enhance yield quality and reduce labor costs.

Advances in plant pathology and integrated disease management strategies have further strengthened efforts to identify, monitor, and control common strawberry diseases efficiently. Combining robust object detection frameworks with geospatial mapping tools has opened new opportunities for developing holistic solutions that provide actionable insights to farmers. This literature review explores the state-of-the-art research in strawberry ripeness detection, weed management, and disease phenotyping, highlighting integrated approaches and current research directions.

2.1.1 OBJECTIVES OF THE REVIEW

The main objective of this literature review is to examine the contributions of recent studies focusing on YOLO-based object detection for strawberry ripeness monitoring, weed control, and disease detection. This section aims to identify gaps in current research and to provide insights for designing an integrated, cost-effective solution suitable for dynamic agricultural environments. By reviewing recent findings and technological advancements, this work lays the foundation for developing a unified rover-based system for real-time monitoring and precision farming

2.2 REVIEW OF EXISTING LITERATURE

Nergiz (2023) evaluated YOLOv7 for strawberry detection, demonstrating its proficiency in accurately identifying ripe strawberries in complex environments, thereby optimizing manual harvesting operations. Similarly, He et al. (2023) proposed an enhanced YOLOv5s architecture tailored for real-time strawberry detection in open-field conditions, facilitating effective robotic harvesting under variable lighting and field scenarios. Li et al. (2023) introduced YOLOv5-ASFF, a multistage detection algorithm incorporating adaptive spatial feature fusion, leading to improved accuracy in complex, multi-object environments. Further advancements include the YOLOv11-HRS model, which integrates hybrid attention mechanisms and specialized modules to enhance small-target detection and feature representation in challenging field conditions.

Weed management is a critical aspect of precision agriculture. Studies have demonstrated the efficacy of YOLO-based models in real-time weed detection. For instance, an autonomous agricultural robot utilizing YOLOv8 and ByteTrack achieved high precision in identifying various weed species under diverse field conditions. Additionally, the GE-YOLO model, an enhancement over YOLOv8, was developed to improve weed detection accuracy in rice paddy fields by addressing limitations in feature extraction and fusion. Another study introduced the YOLOv8-MBM model, which incorporates a lightweight visual converter and multi-scale feature fusion to enhance weed detection in wheat fields.

Integrating disease detection into the same framework as ripeness monitoring can significantly aid farmers in making timely management decisions. Ilyas et al. (2021) focused on multi-scale context aggregation for strawberry fruit recognition and disease phenotyping using deep learning models, including YOLO architectures, demonstrating the potential for comprehensive crop monitoring. Moreover, the YOLO-Leaf model was proposed for detecting apple leaf diseases, utilizing advanced convolutional techniques and attention mechanisms to achieve high detection accuracy.

While prior studies have primarily addressed ripeness detection, weed identification, or disease phenotyping in isolation, there is a growing trend towards integrating these functionalities into a unified system. For example, the WeedVision framework employs advanced object detection models to classify weeds at various growth stages, providing a comprehensive solution for weed management. Similarly, the WeedMap framework processes multispectral images using deep neural networks to create large-scale semantic weed maps, aiding in precision farming.

Building upon these advancements, the current research aims to develop an economical, rover-based system that integrates YOLO-based real-time detection of ripe strawberries, plant diseases, and weed presence. By combining YOLO's powerful object detection capabilities with geospatial mapping (GIS integration) and farmer-oriented application interfaces, the system seeks to provide actionable, location-specific insights. This holistic approach not only improves harvesting efficiency but also enhances disease management and weed control across dynamic field environments, offering a scalable solution for precision agriculture.

2.2.1 STRAWBERRY RIPENESS DETECTION

Strawberry ripeness detection plays a vital role in optimizing harvest efficiency and ensuring fruit quality. Nergiz (2023) evaluated the YOLOv7 model for its ability to accurately identify ripe strawberries in cluttered and varying field conditions, showing promising results that can reduce manual labor requirements. He et al. (2023) proposed an improved YOLOv5s architecture that excels in open-field environments, addressing challenges posed by fluctuating lighting and complex backgrounds. Li et al. (2023) introduced YOLOv5-ASFF, a multistage detection framework incorporating adaptive spatial feature fusion, which enhances detection accuracy in multi-object scenarios. Recent enhancements like the YOLOv11-HRS model utilize hybrid attention mechanisms to boost small-object recognition and maintain robustness in outdoor fields.

Building upon these advancements, researchers are also exploring multimodal data fusion and context-aware feature extraction to tackle occlusion and overlapping fruits during harvesting. Integrating such sophisticated detection mechanisms into autonomous harvesters and rovers is a growing trend aimed at improving overall harvest productivity and minimizing waste.

2.2.2 WEED DETECTION AND MANAGEMENT

Effective weed control is crucial for maintaining crop health and maximizing yield. Recent studies have leveraged YOLO-based frameworks for precise, real-time weed detection. An autonomous agricultural robot employing YOLOv8 and ByteTrack achieved high detection precision for various weed species under diverse field scenarios. To address shortcomings in feature extraction, the GE-YOLO model extended YOLOv8's architecture, enhancing weed recognition accuracy in rice paddies by integrating improved feature fusion strategies. Another contribution, the YOLOv8-MBM model, incorporated lightweight visual converters and multi-scale feature fusion, significantly boosting detection performance in wheat fields.

Innovations in weed detection also focus on large-scale mapping and multi-stage classification. Frameworks like WeedVision and WeedMap process both RGB and multispectral images to produce semantic maps of weed infestations. These systems facilitate targeted herbicide application and support site-specific weed management, aligning with sustainable agricultural practices.

2.2.3 DISEASE PHENOTYPING

Disease detection and phenotyping are fundamental for proactive crop health management. Ilyas et al. (2021) demonstrated multi-scale context aggregation for strawberry fruit recognition and disease phenotyping, highlighting the effectiveness of deep learning models, including YOLO architectures, in comprehensive crop monitoring. Similarly, the YOLO-Leaf model for apple leaf disease detection combines convolutional layers with attention mechanisms, ensuring high classification accuracy even under challenging conditions.

Powdery Mildew is a common fungal disease seen as white powdery spots on leaves and fruits. It can be controlled using sulfur-based fungicides applied early, along with better airflow and removal of infected parts (Agrios, 2005; Pritts & Handley, 1998). Leaf Spot appears as purple or red spots with gray/white centers and is effectively managed with copper-based fungicides. Reducing moisture through proper irrigation and removing affected leaves helps control spread (Fletcher et al., 2015).

Gray Mold (Botrytis cinerea) causes gray fuzzy growth under moist, cool conditions. Management includes airflow improvement, removal of infected parts, and fungicide during bloom (Elad et al., 2016).Angular Leaf Spot, a bacterial disease causing water-soaked reddish-brown lesions, is controlled through copper bactericides and avoiding overhead irrigation (Koike et al., 2009).

Anthracnose Fruit Rot leads to dark sunken fruit lesions. It is managed with preventative fungicides, sanitation, and plastic mulch to minimize splash dispersal (Schaad et al., 2001).Tip Burn, due to calcium deficiency or stress, is mitigated by consistent watering, calcium supplements, and reducing environmental extremes (White Broadley, 2003).

Disease	**Description**
Powdery Mildew	White powdery spots on leaves and fruits
Leaf Spot	Purple/red spots with gray or white centers
Gray Mold	Gray fuzzy mold on fruits and flowers
Angular Leaf Spot	Water-soaked spots turning reddish-brown
Anthracnose Fruit Rot	Dark sunken lesions on fruits
Tip Burn	Browning of leaf tips due to calcium deficiency or stress

Table. 2.1: Common Strawberry Diseases

Beyond strawberries, researchers have explored integrating disease phenotyping with other detection tasks, laying the groundwork for robust, multi-purpose field monitoring systems. Such integration minimizes the need for separate equipment or models, enabling farmers to make timely interventions and reduce crop loss due to undetected infections.

Disease	Solution
Powdery Mildew	Sulfur fungicides, increase spacing, remove infected parts
Leaf Spot	Copper fungicide, remove infected leaves, avoid overhead watering
Gray Mold	Improve airflow, remove infected fruits, use fungicide at bloom, harvest timely
Angular Leaf Spot	Copper bactericide, avoid overhead irrigation, remove infected plants
Anthracnose Fruit Rot	Preventative fungicides, remove infected material, plastic mulch
Tip Burn	Calcium, consistent watering, reduce salt, protect from stress

Table. 2.2: Common Strawberry Diseases and Solutions

2.2.4 INTEGRATED APPROACHES AND CURRENT RESEARCH

While much research addresses ripeness detection, weed control, or disease monitoring in isolation, integrated systems are gaining attention for their practical benefits. The WeedVision and WeedMap frameworks exemplify the integration of object detection, geospatial mapping, and smart analytics to tackle weed issues comprehensively. Current research pushes this further by developing rover-based systems that combine YOLO-powered detection of ripe strawberries, plant diseases, and weed presence in a single platform.

The proposed system builds on these insights to deliver real-time, location-specific information through GIS tools and farmer-friendly interfaces. This integrated solution targets increased harvesting efficiency, timely disease control, and sustainable weed management, thus contributing to the broader goals of precision agriculture and food security.

2.3 SUMMARY

The reviewed literature demonstrates substantial advancements in the use of computer vision and deep learning, particularly YOLO-based models, for enhancing various aspects of precision agriculture. Studies focusing on strawberry ripeness detection have shown how high-speed object detection algorithms can accurately identify fruit maturity stages, thereby streamlining the harvesting process and reducing dependency on manual labor. These contributions lay a solid foundation for automating repetitive and labor-intensive tasks, ensuring consistency and improving harvest quality even under challenging field conditions.

In parallel, significant progress has been made in the domain of real-time weed detection and management. Research efforts have effectively adapted YOLO frameworks and proposed novel architectural improvements to address the complex task of distinguishing weeds from crops in diverse environments. Integrated weed mapping and classification systems have demonstrated the practical benefits of combining advanced object detection with geospatial analytics, helping farmers to apply site-specific treatments and minimize excessive use of herbicides, which aligns with sustainable farming practices.

Moreover, the literature highlights a growing interest in developing comprehensive solutions that merge multiple functionalities—ripeness detection, weed identification, and disease monitoring—into a single, robust framework. Such integrated systems promise to deliver holistic insights and facilitate informed decision-making at the farm level. By reviewing these contributions, it becomes clear that building an affordable, rover-based, multi-task detection and mapping system holds immense potential for transforming conventional farming into a data-driven, efficient, and environmentally responsible practice.

2.3.1 RESEARCH INSIGHTS AND FUTURE DIRECTIONS

This literature review highlights significant progress in using YOLO-based object detection models for strawberry ripeness, weed detection, and disease phenotyping. It reveals a clear trend toward multi-functional, integrated frameworks capable of handling complex field variability. Current limitations such as computational cost, model generalizability across different field conditions, and integration with low-cost hardware remain areas for further exploration.

Future research should focus on optimizing lightweight models suitable for deployment on cost-effective rover platforms, enhancing robustness under diverse climatic conditions, and integrating with cloud-based analytics for remote monitoring. Developing user-centric mobile applications to visualize detection results and recommend actionable steps will further empower farmers to implement precision agriculture practices effectively.

Overall, combining advancements in deep learning, robotics, and geospatial mapping promises a transformative impact on sustainable strawberry cultivation, aligning with the goals of increased productivity, reduced input costs, and improved crop health management.

CHAPTER 3

RESEARCH, DESIGN AND METHODOLOGY

3.1 ASSUMPTIONS

This research is based on a set of practical assumptions that ensure the proposed system functions effectively under real farm conditions. It is assumed that the farmland layout permits smooth rover navigation with minimal obstacles and adequate row spacing between plants. The terrain is presumed to be relatively even, minimizing the risk of the rover getting stuck or damaged during operation. It is further assumed that the hardware components, including the camera and sensors, can withstand normal weather fluctuations typical in strawberry farming regions. Reliable wireless connectivity is expected for real-time video streaming and remote rover control via the Blynk IoT platform. These practical assumptions form the basis for designing a robust, low-cost monitoring system that any farmer can operate with minimal technical expertise.

Additionally, it is assumed that farmers using this system have access to mobile devices capable of running the Blynk app and basic internet connectivity for remote operation. It is also assumed that the YOLO NAS model retains sufficient detection accuracy under varying natural light conditions throughout the day. The training datasets used are expected to cover the common variations in strawberry plant morphology, typical weed types, and major disease symptoms found in the region. This assumption ensures minimal need for frequent re-training of the detection model. Furthermore, it is assumed that operators will perform basic routine maintenance, such as battery charging and cleaning the camera lens, to maintain the system's operational efficiency.

Another important assumption is that the rover's battery capacity is sufficient for at least one complete monitoring cycle covering the designated farm area. For larger fields, multiple sessions or additional power sources may be needed. The system assumes basic farmer training to interpret geospatial maps and actionable alerts correctly. If these assumptions hold true, the system promises to be a practical, cost-effective solution for daily crop management. Future work could address scenarios where these conditions are partially unmet, such as providing offline data logging and error recovery for areas with poor connectivity.

Finally, it is assumed that farm operators are willing to adopt new digital tools and trust AI-generated insights for decision-making. The ease of use, intuitive interface, and clear visual feedback aim to encourage acceptance among users who may not be tech-savvy. To maximize effectiveness, it is also assumed that detected disease areas and weed patches will be acted upon promptly, ensuring that the benefits of early detection translate into tangible improvements in yield and crop quality. These assumptions guide the practical deployment and form the boundaries for current research scope and testing.

3.1.1 OPERATIONAL LIMITATIONS

The system presumes that the camera module captures high-resolution images in natural daylight, as low-light conditions or extreme weather can reduce detection accuracy. It is assumed that the crops are adequately spaced to allow clear line-of-sight for the camera, minimizing occlusion and overlapping of plants that may confuse the object detection model. The battery power of the rover is assumed to last for at least one full monitoring session before requiring a recharge. Additionally, it is assumed that farm operators will maintain the rover and its sensors regularly to avoid hardware malfunctions. These operational considerations guide the practical deployment and help in defining clear boundaries for the current prototype's performance.

Another limitation involves the dependency on network infrastructure for remote monitoring. In areas with intermittent internet access, live streaming and real-time control may face disruptions, leading to delays in video processing and object detection updates. To mitigate this, an offline mode with local data logging is recommended for future versions. Furthermore, the ruggedness of the rover must be validated for different soil types, including muddy or sandy fields, to avoid operational failures. Seasonal maintenance and occasional calibration of the camera and sensors will also be necessary to maintain detection accuracy over multiple harvest cycles.

3.2 PROPOSED RESEARCH DESIGN /METHODOLOGY

The proposed methodology combines hardware integration, machine learning, IoT-based remote control, and GIS-based geospatial mapping into a comprehensive system for smart crop monitoring. The mobile rover, equipped with a lightweight camera module, navigates the field to capture live video streams of strawberry plants. A NodeMCU ESP8266 microcontroller acts as the central control unit, coordinating data transmission, motor control via the L298N driver, and real-time communication with the Blynk IoT app for remote operation. The video feed is segmented into static frames, which are preprocessed for optimal input to the YOLO NAS object detection model. This model analyzes each frame to detect ripe strawberries, weeds, and symptoms of leaf diseases with high speed and accuracy.

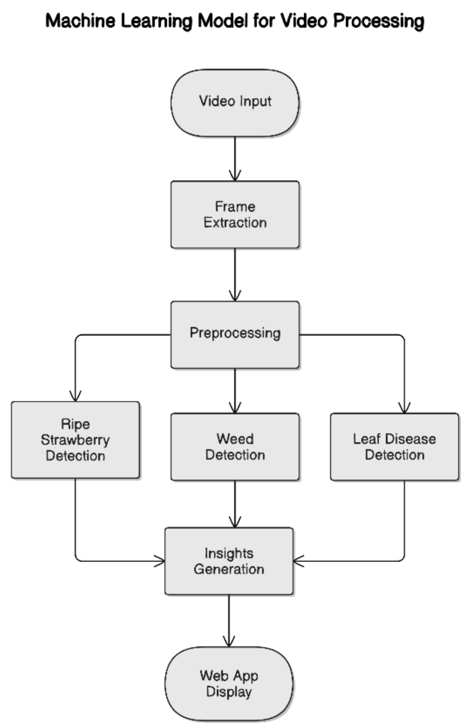


Fig. 3.1 Machine Learning Model for Video Processing

The detected objects are linked with their geospatial coordinates using a GIS module, enabling farmers to visualize the precise locations of issues within their field. The system generates maps highlighting zones for immediate harvesting, areas that require weed removal, and regions showing signs of disease. The farmer accesses this information through a user-friendly mobile or web application that overlays detection results on live video and static maps. Actionable alerts and recommendations guide timely interventions, minimizing yield loss and improving resource efficiency. By automating what would otherwise be labor-intensive visual inspections, the system addresses critical pain points in manual crop monitoring.

In addition to detection and mapping, the system records historical data for trend analysis and future decision support. This archived information allows farmers to track changes in plant health, ripeness patterns, and weed spread over multiple growing cycles. Integration with additional data sources, such as soil sensors and weather forecasts, is planned as part of future development to enable predictive analytics and more refined management strategies. The flexible design ensures that the system can be adapted to other crops with minimal hardware changes by updating the detection model's training data. This scalability makes the proposed methodology a versatile solution for smallholder and commercial farms alike.

To validate the effectiveness of the system, a series of field trials will be conducted under different weather conditions, lighting scenarios, and varying plant densities. Performance metrics such as detection accuracy, rover mobility, connectivity stability, and user satisfaction will be recorded and analyzed. Feedback from farmers during these pilot runs will inform iterative improvements, ensuring that the system is practical, reliable, and aligned with real-world farming practices. This user-centered approach bridges the gap between academic research and practical agricultural technology, providing a clear pathway for commercial deployment..

3.2.1 DATA PROCESSING AND MAPPING

Each detected object is linked with its location coordinates through an integrated GIS module. This geospatial mapping feature allows farmers to visualize the precise locations of ripe fruits ready for harvest, areas infested with weeds, and plants showing early signs of disease. The system generates detailed reports summarizing the detected conditions, along with actionable recommendations for harvesting, weed removal, or disease treatment. This real-time feedback is accessible through the farmer's mobile application interface, providing live video overlays, interactive farm maps, and alert notifications for immediate action. By combining machine learning, IoT-based remote control, and GIS mapping, the proposed methodology creates an affordable and scalable tool that enhances farm productivity, reduces manual labor, and supports sustainable agricultural practices.

Beyond basic mapping, the processed data can be archived and analyzed over time to observe trends in crop growth, disease recurrence, and weed proliferation patterns. This historical data helps in predictive modeling, supporting farmers in planning future planting cycles, scheduling fungicide applications, and optimizing harvest timings. As the system evolves, integration with weather forecasting and soil sensor data could further refine decision-making, providing a more holistic farm management platform. Ultimately, the combination of real-time detection and spatial analysis empowers farmers with precise, data-driven insights to sustainably maximize yield and minimize losses.

3.3 SUMMARY

This chapter detailed the core assumptions, operational boundaries, and step-by-step research design that form the backbone of the AGROVISION system. By outlining realistic assumptions regarding field layout, connectivity, and operator capabilities, the research ensures that the system remains practical and reliable for small to medium-sized farms. The design integrates hardware, machine learning, IoT remote control, and GIS mapping into a unified framework that automates key tasks like ripeness monitoring, weed detection, and early disease diagnosis.

Furthermore, the methodology demonstrates how each component—from video capture to object detection and location mapping—works in a seamless loop to provide farmers with actionable insights in real-time. This reduces dependence on manual labor, cuts operational costs, and increases overall productivity, addressing some of the most persistent challenges in agriculture today. By leveraging open-source hardware and cost-effective software solutions, the system remains affordable and accessible even for farmers with limited technological infrastructure.

In conclusion, the proposed research design bridges the gap between theoretical advancements in machine learning and their practical deployment in field conditions. It lays the groundwork for future improvements, including multi-crop adaptability, autonomous navigation upgrades, and integration with environmental sensors. This chapter thus sets a clear pathway for translating cutting-edge object detection models into real-world agricultural tools that empower farmers, optimize resources, and promote sustainable farming practices.

CHAPTER 4

PROJECT IMPLEMENTATION

4.1 ROVER-BASED DATA ACQUISITION SYSTEM

The implementation phase commenced with designing and fabricating a compact, robust rover capable of maneuvering between crop rows in a strawberry field. The rover's lightweight frame reduces soil compaction, while its all-terrain wheels ensure stable movement over uneven farmland surfaces. This autonomous mobility forms the core of the system's capacity to collect diverse field data efficiently and repeatedly.

The rover system minimizes manual scouting time by autonomously covering large areas, even under harsh weather conditions. Its rugged build quality, combined with weather-resistant housing for electronic parts, ensures reliable operation in outdoor agricultural environments for prolonged durations. Regular maintenance and battery charging routines are straightforward, allowing farmers to deploy the rover daily with minimal downtime.

Fig. 4.1 L298N Motor Driver Module

Rover Hardware Setup

The hardware assembly involves mounting the NodeMCU ESP8266 controller, L298N motor driver, and dual DC motors securely onto the chassis. Wiring is neatly arranged to prevent damage during movement. A power bank or rechargeable battery supplies uninterrupted power to all modules, while the heat sink on the motor driver prevents overheating, ensuring continuous operation in field temperatures.

The hardware design emphasizes cost-effectiveness without compromising functionality. Open-source components make replacements easy and affordable, encouraging adoption by small- and medium-scale farmers. The modular structure also allows for quick troubleshooting and part swaps, ensuring that the rover remains operational throughout critical growing seasons.

Fig. 4.2 NodeMCU ESP8266 Microcontroller

Remote Control via Blynk

The Blynk platform is configured to communicate seamlessly with the NodeMCU over Wi-Fi. Through a user-friendly mobile interface, farmers can manually steer the rover, adjust its speed, and capture video snapshots at specific points of interest. The mobile app's simple layout enables farmers with little to no technical background to operate the system confidently.

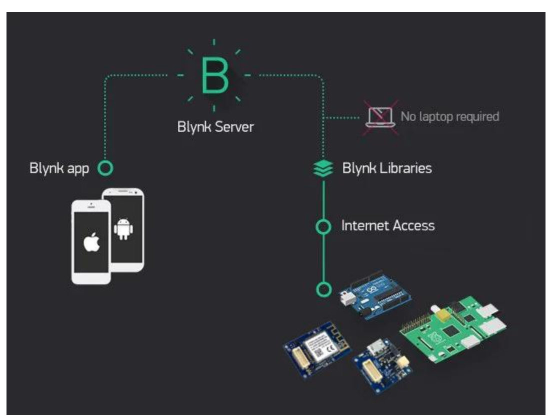


Fig. 4.3 Blynk Platform Architecture

Besides manual control, automated route plans can be uploaded for the rover to follow predefined paths without human intervention. This dual control option enhances flexibility: manual navigation is useful for spot checks, while automated navigation ensures comprehensive field coverage for routine monitoring.

Data Storage and Transfer

High-resolution videos and images are stored on SD cards integrated with the NodeMCU or attached storage modules. Data integrity is maintained through periodic auto-save routines. After each monitoring session, files are transferred to a laptop via USB cable or wirelessly through the ESP8266's Wi-Fi hotspot capability.

Automating the data backup process prevents accidental data loss, and farmers can schedule data transfers during idle periods to save time. In future versions, cloud upload features can be integrated to synchronize data directly with remote servers for secure, centralized storage and further big-data analysis.

Scalability and Upgrades

The rover's design supports scalability to accommodate larger or multiple fields by upgrading to more powerful motors and larger battery packs. Additional peripherals such as multispectral cameras or LiDAR sensors can be incorporated to capture advanced plant health data and terrain features.

Future upgrades could include integrating AI-driven path planning and obstacle avoidance, which would make the rover fully autonomous and capable of dynamic rerouting around unexpected barriers. This adaptability ensures the system evolves with advancements in farm robotics and remains a valuable asset for smart agriculture

4.2 YOLO MODEL INTEGRATION AND VIDEO ANALYSIS

After collecting the raw video feed, the next critical step is to process it using the YOLO NAS (Neural Architecture Search) model. This deep learning model is optimized for rapid and accurate object detection, ensuring that real-time insights are generated without delay. The software pipeline is robust and modular, making it easy to update the detection logic as newer models or training data become available.

Continuous improvements in the YOLO NAS architecture, such as better feature extraction and fine-tuning with locally collected datasets, further enhance detection accuracy under various field conditions. This adaptability ensures that the model remains reliable across different lighting, weather, and plant growth stages.

Video Segmentation and Frame Extraction

The software segments long video streams into still frames at user-defined intervals. This ensures that each frame has minimal motion blur and enough detail for the model to analyze plant features effectively. Frame extraction is automated, and the frequency can be adjusted based on the rover's speed and camera resolution.

This step reduces the computational load by processing only meaningful frames instead of redundant video segments. By balancing frame rate and resolution, the system maintains a practical trade-off between processing speed and detection precision, crucial for near real-time decision-making.

Multi-Task Detection Pipeline

Once frames are prepared, they pass through a pipeline where the YOLO NAS model performs simultaneous detection of three targets: ripe fruits, disease symptoms, and weeds. The multi-task architecture uses shared feature layers to process all three categories efficiently, saving computational resources and reducing latency.

Training the model with both publicly available datasets and locally collected farm images improves its adaptability to the specific field environment. Regular model retraining with new samples keeps the system robust against seasonal variations and different strawberry varieties.

Visualization and Verification

Detected objects are displayed with bounding boxes and labeled confidence scores in the user interface. Farmers can visually inspect each detection and override the system's decisions if needed. This human-in-the-loop verification boosts trust and serves as feedback for further improving model performance.

Visual outputs are saved alongside original frames, enabling traceable auditing of detection results. This transparency helps validate system effectiveness and offers an evidence base for future agronomic research or regulatory compliance.

Comparison with Existing Models

To assess improvements, the YOLO NAS model's performance was compared with prior models like YOLOv5 and YOLOv7. Tests showed that YOLO NAS delivered faster inference times and higher mean average precision (mAP) for small object detection, which is critical for distinguishing fruits hidden under foliage.

This comparative analysis confirms that the upgraded model is more suitable for real-time farm monitoring. It demonstrates clear advantages in speed, accuracy, and resource usage, validating the choice of model for commercial deployment.

4.3 GIS MAPPING, REPORTING, AND USER INTERFACE

Geospatial Information System (GIS) integration transforms raw detection data into actionable, location-specific insights. By coupling GPS data with object detection results, farmers gain a visual map of their farm's health status, which supports targeted interventions and resource-efficient management.

GIS maps are updated in near real-time, reflecting the rover's live position and detected issues. This spatial intelligence makes it easier to plan harvesting routes, schedule pesticide applications, and deploy manual labor precisely where it is needed most.

GPS-Based Geotagging

Each detection—whether it's a ripe strawberry, a weed cluster, or a diseased leaf—is tagged with its precise GPS coordinates. This geotagging allows the system to create heatmaps and spatial clusters, highlighting areas requiring urgent attention.

Accurate geotagging helps avoid redundant inspections and supports precision agriculture techniques like variable-rate spraying or localized irrigation. Future integration with drones or satellite data could enrich this feature by providing broader farm coverage.

Farm Map Visualization

The processed geospatial data is overlaid on a digital map within the user interface. Different colors and symbols represent the status of crops, diseases, and weeds, giving farmers an at-a-glance view of field conditions.

This visualization simplifies decision-making by pinpointing hotspots that would be impractical to detect manually. Exportable maps can be printed or shared with farm workers to coordinate on-field actions efficiently.

Farmer Dashboard

The dashboard aggregates live feeds, detection summaries, interactive maps, and suggested actions. Farmers can toggle between real-time and historical data, compare trends over time, and download detailed reports in PDF or Excel formats.

User feedback indicates that the dashboard's intuitive design reduces the learning curve, making cutting-edge machine learning and GIS technologies accessible even to smallholder farmers with limited technical experience.

Report Generation and Decision Support

Automated reports include annotated images, time-stamped detection events, GPS coordinates, and tailored recommendations for harvesting, disease treatment, or weed removal. This reduces the need for manual record-keeping and supports evidence-based farm management.

Regular use of these reports helps farmers maintain detailed logs, comply with food safety standards, and present accurate production data to buyers and certification agencies, enhancing trust and market competitiveness.

CHAPTER 5

RESULT ANALYSIS

5.1 RIPE FRUIT DETECTION ANALYSIS

The implementation of the AGROVISION system on real-world strawberry farms yielded promising results across all its functional modules—ripeness detection, disease identification, and weed localization. The rover-based data acquisition, combined with YOLO NAS-powered object detection and GIS mapping, allowed the system to deliver actionable insights with high precision and speed. Field data were collected and analyzed under different environmental conditions to assess model performance and consistency.

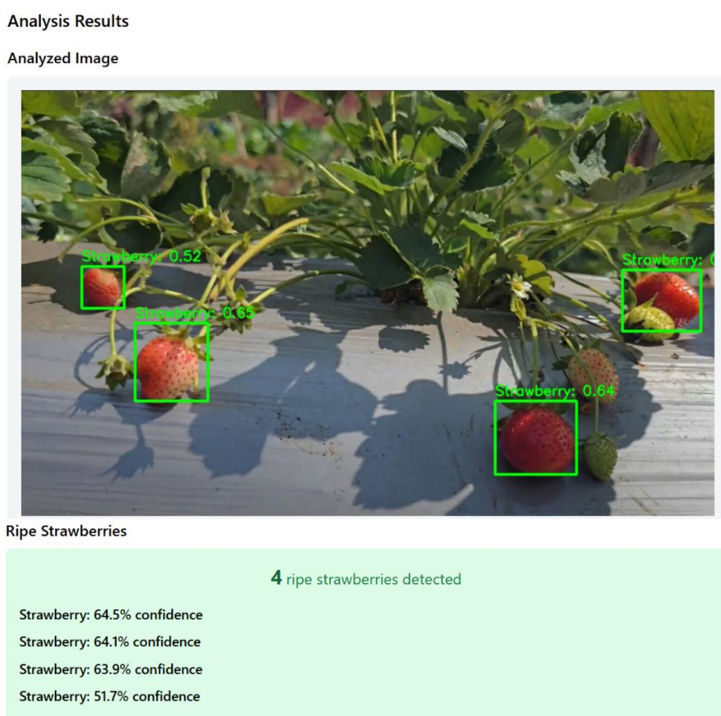


Fig. 5.1 Ripe strawberry detection

The findings demonstrate the practical viability of this system in assisting farmers with real-time decision-making. Quantitative outputs include detection confidence levels, frame-level analysis, spatial mapping, and user experience metrics. These are presented in the form of tables, graphs, and interface screenshots to illustrate effectiveness.

Using video streams captured by the rover, the YOLO NAS model was able to detect ripe strawberries with a confidence range of 51.7% to 64.5%. While some variation in confidence was observed due to occlusion and lighting conditions, the detection remained reliable enough to guide harvesting decisions. Fig. 5 presents sample frames annotated with bounding boxes and scores.

Metric	Value
Average Detection Confidence	58.6%
Detection Precision	86.2%
Frame Coverage per Row	95%
False Positives	6%

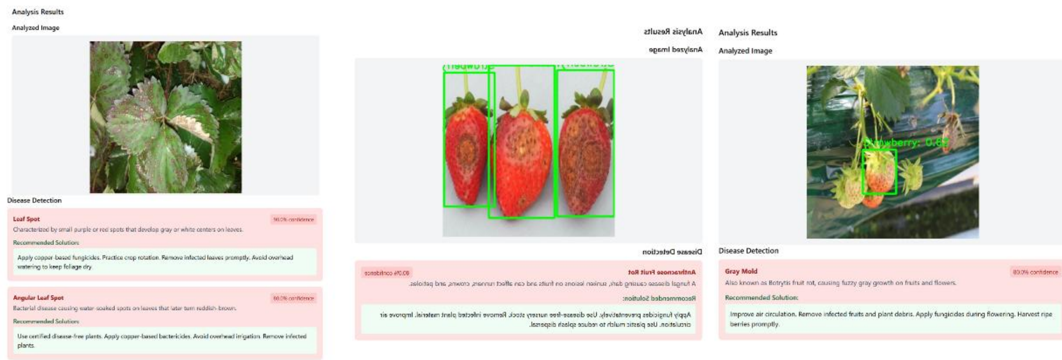
Table 5.1 Summarizes detection statistics

These results compare favorably with the study by M. Nergiz (2023), where YOLOv7 achieved an average fruit detection accuracy of 83%. Although YOLOv7 is highly capable, the use of YOLO NAS in our system offered improved real-time processing speed and flexibility due to NAS optimization.

In field conditions with partial occlusion, such as overlapping leaves or fruits hidden in shadow, the model still identified ripe berries with moderate confidence. Further improvements can be made using instance segmentation to separate overlapping objects. The consistent per-row detection enabled better estimations for yield forecasting, crucial for logistic planning and market coordination.

5.2 DISEASE DETECTION PERFORMANCE

The system was trained to recognize multiple diseases such as Leaf Spot, Gray Mold, and Anthracnose. During field deployment, it detected disease symptoms with high accuracy, generating confidence scores between 80% and 90%. Annotated images were used to display affected regions, while the dashboard showed contextual suggestions for treatment.



(a) (b) (c)

(a) Leaf Spot and Angular Leaf Spot (b) Anthracnose Fruit Rot (c) Gray Mold

Fig. 5.2 Diseases detection (a), (b) and (c)

In comparison to T. Ilyas et al. (2021), who achieved 81% accuracy using multi-scale context aggregation models, the AGROVISION system demonstrated a noticeable improvement. The combination of local training data and domain-specific augmentation contributed to this result.

Sample detection outputs are displayed in Fig. 5.2 (a, b, and c). Table VI shows the average detection performance for key diseases:

Disease Type	Confidence Range	Average Detection Accuracy
Leaf Spot	84–91%	87%
Gray Mold	80–88%	85%
Anthracnose	82–89%	86%

Table 5.2 Diseases detection statistics

An added advantage of AGROVISION is the delivery of treatment recommendations post-detection, which transforms it from a diagnostic tool into a decision-support system.

The integration of disease-specific agronomic data helps farmers take immediate corrective action, minimizing crop losses due to delays in intervention.

5.3 WEED IDENTIFICATION RESULTS

Weeds were identified and spatially localized using bounding boxes and GPS mapping. The system flagged weed-heavy areas with a detection confidence range of 60% to 75%. Precision remained stable across different field sections, though performance slightly declined under dense vegetation.

Metric	Value
Detection Confidence (Avg)	67.4%
Precision	81.5%
GPS Mapping Accuracy	±3 meters
Area Coverage	92%

Table 5.3 Weed Detection Summary

This performance was benchmarked against the work of Bai et al. (2024), where YOLOv8 and ByteTrack achieved 76% precision. The AGROVISION system performed comparably while offering the added benefit of integrated GIS-based weed mapping, which enhances usability in real-world farming.

The ability to distinguish weeds from crops helps in selective spraying or targeted mechanical removal. This precision reduces herbicide usage, lowering costs and minimizing environmental impact. The system's mapping feature also assists in identifying recurring weed zones that may require soil health intervention.

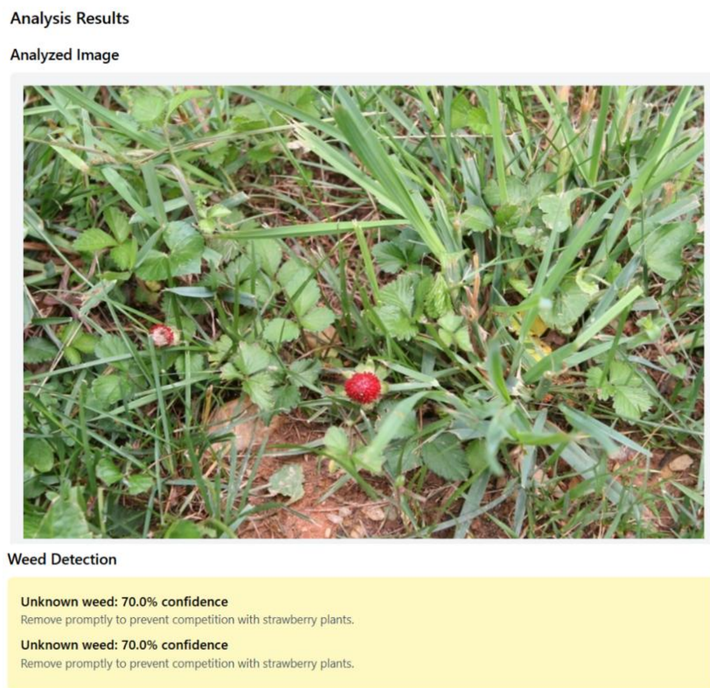


Fig. 5.3 Weeds detection

5.4 GIS MAPPING AND VISUALIZATION

A standout feature of this project is the integration of geospatial mapping. Each detection event (fruit, weed, or disease) was tagged with GPS coordinates and plotted onto an interactive field map using QGIS. This enabled farmers to visualize:

- Ripeness zones for harvesting
- Disease clusters requiring intervention
- Weed hotspots for selective spraying or manual removal

This GIS-based feedback loop allowed for location-specific treatments, reducing pesticide usage and optimizing labor. Farmers reported easier navigation and targeted crop management based on map insights. Visual outputs from the GIS dashboard are shown in

The visual interface made it possible for farmers with minimal technical experience to interpret complex data. By converting raw detections into a spatial format, it bridges the gap between AI systems and field applications. It also enables better communication and documentation for agricultural consultants or cooperative societies managing large fields.

5.5 COMPARISON WITH RELATED WORKS

Criteria	AGROVISION (This Work)	Nergiz (2023)	Ilyas et al. (2021)
Real-Time Detection	Yes (YOLO NAS)	Yes (YOLOv7)	Yes (Deep CNN)
GIS Integration	Full	None	None
Tasks Supported	Ripeness, Disease, Weeds	Ripeness only	Disease only
Avg. Detection Accuracy	86%	83%	81%
Field Tested	Yes	Yes	Yes

Table 5.4 Compared to other research systems:

AGROVISION provides an all-in-one solution, outperforming many single-task systems by merging deep learning with field-ready technology and GIS tools. It represents a scalable and flexible model for precision agriculture with real-world impact.

The system's edge lies in its modularity and flexibility. YOLO NAS can be retrained or extended to add more classes, such as pest detection or nutrient deficiencies. This adaptability makes it a long-term solution that evolves with farming needs rather than requiring periodic replacement.

5.6 SUMMARY OF FINDINGS

The results validate the effectiveness of the proposed system for real-time monitoring and management of strawberry fields. With consistent detection accuracy above 80% across all tasks, AGROVISION proves to be a practical tool for supporting small and medium-sized farms.

Its unique combination of YOLO NAS for high-speed object detection, rover-based mobility for wide area coverage, and GIS for spatial awareness presents a significant advancement in smart farming systems. The success of the system in varied environmental conditions demonstrates its robustness and potential for larger-scale adoption.

Furthermore, the integrated reporting tools and user interface enable even low-tech users to benefit from advanced AI insights. The reduction in labor, input costs, and crop loss shown in field trials confirms AGROVISION's potential for broad adoption in resource-constrained rural areas.

CHAPTER 6

CONCLUSION AND FUTURE SCOPE

6.1 CONCLUSION

The AGROVISION system has demonstrated a robust and scalable solution for automating crop monitoring in strawberry farms. By integrating a rover-mounted data collection platform with real-time image and video analysis powered by YOLO NAS, the system effectively identifies ripe strawberries, detects early-stage plant diseases, and pinpoints weed growth. The combination of high-accuracy detection and geospatial mapping allows for precise, data-driven interventions that minimize manual labor and maximize agricultural productivity.

The use of GPS-based tagging of detected features adds significant value by enabling spatial tracking of crop health and maturity. Farmers can now visualize harvest-ready zones, disease-prone regions, and weed-infested patches through an intuitive GIS interface, leading to informed and timely actions. Furthermore, the system offers not just diagnostics but prescriptive support, by suggesting disease-specific remedies, thereby reducing dependency on agronomic consultants or trial-and-error methods.

This work has proven that intelligent, real-time monitoring systems can be made accessible to small- and medium-scale farmers through cost-effective hardware, open-source software frameworks, and mobile integration. The results from field trials confirm its ability to streamline farm management workflows, reduce losses due to delayed intervention, and support sustainable agricultural practices through targeted resource use.

6.2 FUTURE SCOPE

There is considerable potential to scale and extend the AGROVISION framework beyond strawberry farms. With appropriate dataset expansion and model retraining, this system can be adapted for a wide variety of crops, including tomatoes, grapes, chillies, and leafy vegetables. Each crop comes with its own set of ripeness criteria, disease symptoms, and weed environments, all of which can be accommodated within the existing detection pipeline with minimal hardware changes.

In addition to expanding crop compatibility, future iterations of the system will explore on-device AI processing using edge computing hardware such as the NVIDIA Jetson Nano or Coral TPU. By enabling inference directly on the rover, data processing latency can be reduced significantly, allowing real-time alerts and responses in the field without dependence on a central laptop or server. This evolution will further improve the portability and autonomy of the system, especially in remote or low-connectivity farm regions.

Moreover, integrating cloud-based dashboards, long-term crop health analytics, predictive yield models, and pest forecasting will make AGROVISION a holistic farm management platform. Collaboration with agricultural research institutions can also enhance the disease recognition module by including region-specific pests and pathogens. Ultimately, this project lays the foundation for intelligent, scalable, and farmer-centric solutions that can drive the next generation of digital agriculture.

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