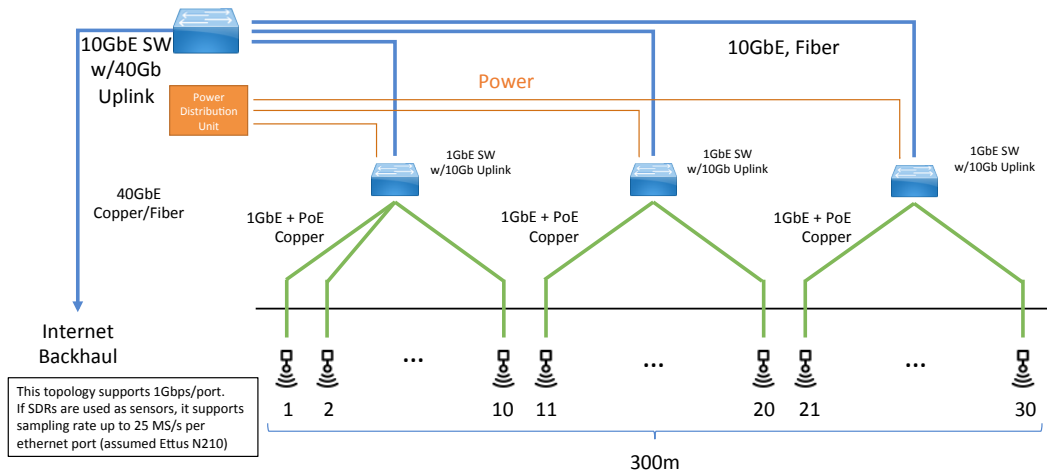


# Development of a Robotic Center Pivot for ML/AI Enabled Near-Field Sensing, Edge-Computing, and Control for Agricultural Experimentation “At Scale”

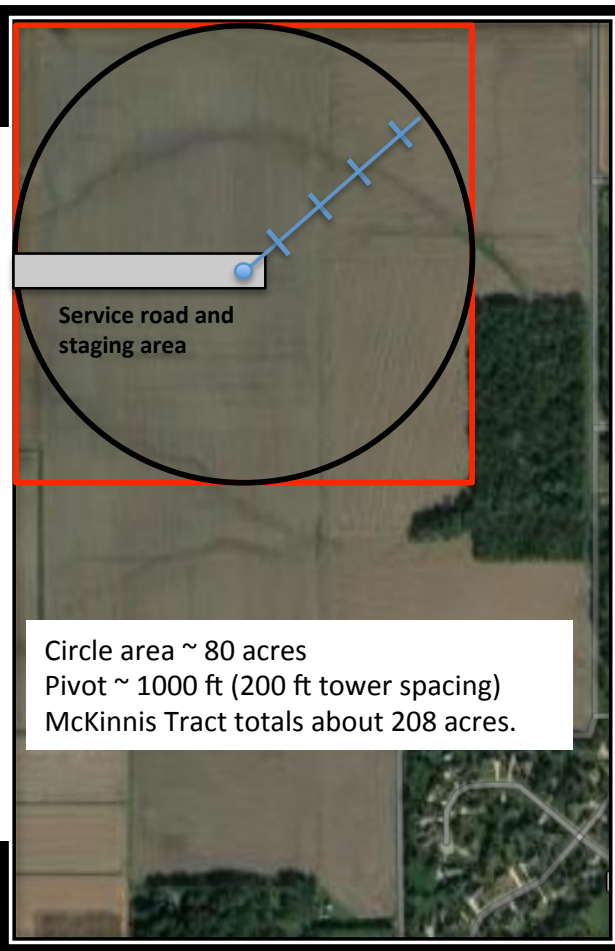
J. V. Krogmeier, D. Buckmaster, J. Evans, C. G.  
Brinton, D. J. Love, C.-C. Wang

# The Proposed Instrument

- ❑ Commercially available irrigation system as a moveable platform for:
  - + Sensing: soil, water, plant, micro-climate, robotic scouting and tissue sampling
  - + Actuation: water, fertilizer, crop protection, spot tillage or weeding
- ❑ The land below equipped with a dense drainage tile system instrumented for water and soil sensing, drainage control, underground comms.



Agronomy Center for Research and Education (ACRE)



# **The Research Enabled**

# The Enabled Research Activities [1/3]

- ❑ Pheno-typing and management practice studies
  - + Hyperspectral imaging
  - + RGB imaging and video
  - + Lidar, infrared
- ❑ Micro-climate studies
  - + Heat, mass, and momentum transfers between organisms and the atmosphere
  - + Greenhouse gas emissions from ag operations
  - + Solar UV radiation and effects on crops

# The Enabled Research Activities [2/3]

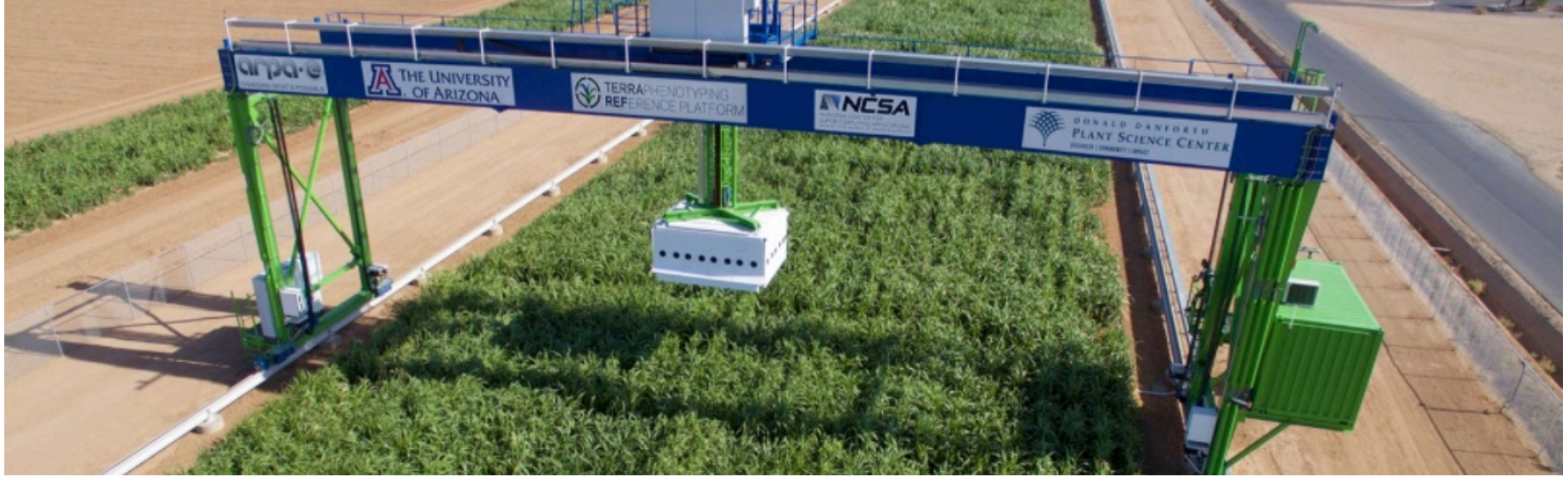
- ❑ Radar – conventional and synthetic aperture
  - + Ground penetrating for mapping soil layers, especially evidence of hardpan and compaction
  - + Soil moisture estimation
  - + At scale tomographic root imaging
  - + Lidar, infrared
- ❑ Robotics – joint control of gantry mounted robotic arms and the pivot assembly
  - + Weeding
  - + Insect scouting
  - + Targeted application of water, fertilizer, and/or herbicides

# The Enabled Research Activities [3/3]

- ❑ mmWave and THz Sensing of crops and atmospheric gases, IoT4Ag style sensors
- ❑ Cornfield (Beans, wheat, pumpkins ...) as a system
  - + Synchronized and simultaneous measurement (spatial and temporal) of all parameters
  - + Study of system under or after stress event (drought, hail, insects, etc.)
  - + Characterize the effect of hard constraints on applied water, nutrients, pesticides, etc.
  - + Measure soil borne carbon over growing season
- ❑ Prove concepts of AI/ML at scale and in real time

# **How the Proposed Instrument Fits in the Puzzle**





## Partner Institutions

- ❑ U. Arizona, U. Illinois, Saint Louis U., G. Washington U., Wash. U., K. State, Clemson
- ❑ D. Danforth Plant Science Center

## Funding: ARPA-E

- ❑ > \$10M, 2015 – 2020

**Primary Use:** Platform for phenotyping of sorghum as a bio-energy source; drought stress

# Compare to TerraRef

- ❑ Order of magnitude larger in area
- ❑ Potential for actuation
- ❑ Deployable at much lower cost
- ❑ Sensing, comms, robotic innovations have the potential to impact farming practice, not just research
- ❑ Potential for lowering cost and democratizing “at scale” agronomic experimentation

# **Design of the Instrument Itself**

# The Pivot Instrument Is ...

- ❑ Three sub-systems:
  - + A nearly conventional irrigation pivot (precision application of water and water soluble crop treatments + sensing)
  - + A data, sensing, robotic actuation pivot as a gantry (limited water, etc. application --- it provides power and high bandwidth wired networking and a standardized port for connecting experimental packages)
  - + Earth buried sensing and instrumented drainage tile with wireless short range connection to the pivot for wireless power and sensor readout
- ❑ Think “minute” hand, “hour” hand on a clock – minute hand cannot pass the hour hand, but it is much faster.
  - + Could have “minute” hand only ... say in Indiana.

# Pivot Instrument Design Considerations [1/2]

- ❑ Networking along the gantry (~300 m):
  - + Several fiber strands and periodically placed power ports and ethernet connections (~10 m spacing)
  - + Need to enable fixed fiber optic link to interface with rotating hub in the center pivot (mmWave short range wireless, optical rotary joint ...)
  - + Must operate in harsh environment and high temperatures
- ❑ Pivot drive design for the “minute” hand pivot. Forward/backward and faster than conventional
- ❑ Pivot rotation point design for minute and hour hand
- ❑ High precision GPS at every tower

# Pivot Instrument Design Considerations [2/2]

- ❑ Instrumented and Controllable Tile Drainage System
- ❑ Beta Instruments and Control Experiments
  - + “Plug-and-play” compatible with research designed sensor packages ... standard interface
  - + Back of the envelop rate calculations. With pivot gantry covering 16 acres per hour ~ 1 Gbps for RGB Flea cameras, Velodyne VLP 32C, Headwall VNIR, and a thermal camera – compared to Purdue pheno-rover machine. Likely need considerably more bandwidth, but it is feasible.
- ❑ Agronomy: experimental plot designs for using such instrument

# **ML/AI Contest for Crop Production Under Constraints**



# NATIONAL CORN YIELD CONTEST



**NATIONAL WINNERS FOR 2020 CORN YIELD CONTEST  
CONDUCTED BY THE NATIONAL CORN GROWERS ASSOCIATION**



| Rank                                   | Entrant Name         | City          | Field | Hybrid Brand | Number      | Yield    |
|--|----------------------|---------------|-------|--------------|-------------|----------|
| <b>A: Conventional Non-Irrigated</b>   |                      |               |       |              |             |          |
| 1                                      | Sam Santini          | Stewartsville | NJ    | DEKALB       | DKC70-27RIB | 381.5595 |
| 2                                      | Landy Thomas         | Cades         | SC    | Pioneer      | P1847VYHR*  | 370.8320 |
| 3                                      | Robert A Santini Jr  | Phillipsburg  | NJ    | Pioneer      | P1197       | 365.6086 |
| <b>B: Conventional Non-Irrigated**</b> |                      |               |       |              |             |          |
| 1                                      | Kevin Kalb           | Dubois        | IN    | DEKALB       | DKC67-44RIB | 385.4405 |
| 2                                      | Rhylan Kalb          | Dubois        | IN    | DEKALB       | DKC67-44RIB | 345.9045 |
| 3                                      | Troy Uphoff          | Findlay       | IL    | DEKALB       | DKC63-57RIB | 323.7983 |
| <b>C: No-Till Non-Irrigated</b>        |                      |               |       |              |             |          |
| 1                                      | Dan Gause Sr.        | Scranton      | SC    | Pioneer      | P1847VYHR*  | 387.0916 |
| 2                                      | Chris Santini        | Stewartsville | NJ    | Pioneer      | P1464AML™*  | 357.4564 |
| 3                                      | Justice Family Farms | Daniels       | WV    | Pioneer      | P1197       | 355.8628 |
| <b>I: Conventional Irrigated</b>       |                      |               |       |              |             |          |
| 1                                      | Don Stall            | Charlotte     | MI    | Pioneer      | P0720AM™    | 476.9052 |
| 2                                      | George Andrew        | Evansville    | WI    | Pioneer      | P0720Q™     | 324.7783 |
| 3                                      | Ashton Peterson      | Bertrand      | NE    | Pioneer      | P1563AML™   | 324.5989 |

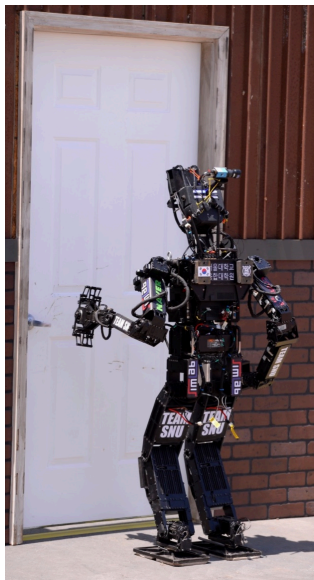
# Imagine ...

- ❑ Create a contest for teams designing algorithms for operating the robotic pivot with a growing season long contest for crop production:
  - + After planting all sensing/scouting must be carried out with the shared platform (collaboration is required)
  - + Water/nutrient application post planting must use pivot platform
  - + Crop protection too ...
- ❑ At the beginning of the year teams write code to operate the sensors and actuators. No hands in the field. No human intervention.
- ❑ To give statistical significance to the ranking we randomize and replicate. “Teams” are the treatments.
- ❑ Apply constraints in rules. Measure runoff. Limit water.



SPECTRUM  
COLLABORATION  
CHALLENGE

USING AI TO UNLOCK THE TRUE POTENTIAL OF THE RF SPECTRUM



UNEARTHING THE SUBTERRANEAN ENVIRONMENT

# SUBTERRANEAN CHALLENGE

Revolutionize how we operate in the underground domain

AGBOT  
CHALLENGE

