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ABSTRACT

In the present scenario robots have become technological leaders. Although there is rapid development in the field of agricultural robotic technologies, but it has been limited in the fruit recognition and precision picking capabilities. In agriculture most of the manual work involves at the harvesting stage. While harvesting humans commit lot of mistakes like plucking over-ripen fruits and some unplucked fruits gets damaged by falling on ground which is a huge loss. To overcome these problems we are designing a robot which will effectively work on harvesting fruits. The main purpose of harvesting robot is to pluck the fruits from the trees without damaging the fruit, and to reduce the burden of human and to speed up the process. Color detection sensor and a robotic arm with gripper-cum-cutter are used to detect and pluck fruits from the tree.