

# Smart Seed Sowing Robot

Garule Pratiksha<sup>1</sup>, Trupti Bhogawade<sup>2</sup>, Gayatri sonawane<sup>3</sup>, Dr.Swati G Gawale<sup>4</sup>

<sup>1,2,3</sup>*Department of Electronics and Telecommunication Engineering, Bharati Vidyapeeth college of engineering, lavale, Pune, India*

<sup>4</sup>*Professor, Department of Electronics and Telecommunication Engineering, Bharati Vidyapeeth college of engineering, lavale, Pune, India*

**Abstract**—The rapid advancement of automation and robotics has significantly influenced modern agricultural practices, particularly in the domain of seed sowing. Traditional sowing methods are highly labor-intensive, time-consuming, and often result in non-uniform seed placement, which negatively impacts crop yield and resource utilization. To address these challenges, researchers have increasingly focused on the development of automated and smart seed sowing robots that enhance precision, efficiency, and operational sustainability. This review presents a comprehensive analysis of recent developments in seed sowing robotic systems, emphasizing design methodologies, control strategies, mechanical mechanisms, and integration with emerging technologies such as IoT, wireless communication, and intelligent control systems. Various robot architectures ranging from manually controlled and semi-autonomous systems to fully autonomous platforms are critically examined. Additionally, energy-efficient designs, including solar-powered and optimized motor control systems, are discussed in the context of sustainable agriculture. The review also highlights real-world performance evaluations, economic feasibility, and environmental benefits reported in recent studies. Through a comparative analysis of existing literature, key re-search gaps related to adaptability, autonomy, precision, and cost-effectiveness are identified. Finally, future research directions are outlined to guide the development of scalable, farmer-friendly, and intelligent seed sowing solutions that support the transition toward precision and smart agriculture.

**Index Terms**—Seed sowing robot, Agricultural robotics, Precision agriculture, Automation in farming, Internet of Things (IoT), Smart agriculture

## I. INTRODUCTION

### Background

Agriculture continues to be a critical sector for global food security, yet it faces persistent challenges such as labor shortages, rising operational costs, and the need for im-proved productivity and sustainability Seed sowing is a foundational agricultural operation, and

inaccuracies in seed placement, spacing, and depth directly in-fluence germination rates, crop uniformity, and overall yield Conventional manual and mechanical sowing techniques are often inefficient, labor-intensive, and unsuitable for precision farming requirements, particularly in small and medium-scale agricultural settings . Advances in robotics, embedded systems, and wireless communication have enabled the development of automated seed sowing robots that aim to overcome these limitations by improving accuracy, efficiency, and repeatability

### Motivation

The motivation for research in seed sowing robotics stems from the growing demand for precision agriculture solutions that reduce human dependency while optimizing re-source utilization Urban migration and demographic changes have resulted in a significant reduction in available agricultural labor, creating an urgent need for autonomous or semi-autonomous farming systems. Recent studies demonstrate that robotic sowing systems can significantly reduce seed wastage, operational time, and long-term costs when compared to traditional methods. Furthermore, the integration of IoT, wireless control, and intelligent sensing technologies has expanded the potential of seed sowing robots beyond basic automation toward smart, data-driven agricultural operations

### Importance of seed sowing robots

Seed sowing robots play a vital role in enabling precision agriculture by ensuring uniform seed distribution and consistent sowing depth, which are critical for optimal crop growth. Modern robotic systems also contribute to sustainable farming by

supporting energy-efficient designs, including solar-powered and optimized motor-based platforms. From an economic perspective, automated sowing robots offer scalable and cost-effective alternatives to large agricultural machinery, making them particularly suitable for small and marginal farmers [6], [29]. Additionally, advancements in autonomous navigation, closed-loop control, and sensor-based decision-making have positioned seed sowing robots as key enablers of next-generation smart agriculture ecosystems.

The primary objective of this review is to systematically analyze recent research and technological advancements in automated and robotic seed sowing systems reported in the literature. This paper aims to compare various mechanical designs, control architectures, communication technologies, and energy management strategies employed in existing seed sowing robots. Another objective is to identify key research gaps related to autonomy, adaptability to diverse field conditions, economic feasibility, and integration with intelligent agricultural frameworks. Finally, the review seeks to outline future research directions that can guide the development of robust, farmer-friendly, and sustainable seed sowing robots for precision and smart agriculture applications.

## II. REVIEW METHODOLOGY

### Database Used

The literature for this review was systematically collected from well-established academic and scientific databases to ensure the credibility and quality of the selected studies. Primary sources included IEEE Xplore for conference papers and robotics-focused research related to autonomous and wireless seed sowing systems. SpringerLink was extensively used to access book chapters and journal articles addressing smart agriculture, robotic seeding mechanisms, and sustainable farming technologies. ScienceDirect and Elsevier-hosted journals were consulted for design-oriented and experimental studies on agricultural robots and automated seed sowing machines. Additionally, AIP Conference Proceedings were reviewed to include recent prototype developments and implementation-focused research in seed sowing robotics.

### Search Strategy

A structured keyword-based search strategy was adopted to retrieve relevant publications related to automated seed sowing and agricultural robotics. Search terms such as “seed sowing robot,” “automated seed sowing machine,” “agricultural robotics,” “precision agriculture robotics,” and “smart seeding system” were used individually and in combination across databases. Boolean operators (AND, OR) were applied to refine results, for example: “seed sowing robot AND IoT” and “agricultural robot AND precision farming.” The search was limited to publications between 2021 and 2025 to ensure that the review reflects recent technological advancements and contemporary research trends. Reference lists of selected review and survey papers were also manually screened to identify additional relevant studies not captured in the initial database search.

### Inclusion Criteria

Studies were included in this review if they focused on the design, development, implementation or evaluation of automated or robotic seed sowing systems. Research articles addressing mechanical mechanisms, control strategies, wireless communication IoT integration, or energy-efficient designs in seed sowing robots were considered relevant. Both experimental prototypes and simulation-based studies demonstrating functional validation or performance analysis were included to provide a comprehensive perspective. Peer-reviewed journal articles, conference papers, and book chapters written in English were selected to maintain academic rigor and consistency.

### Exclusion Criteria

Studies that focused solely on manual or purely mechanical seed sowing machines without automation or robotic control were excluded from this review [17]. Papers addressing agricultural robots for tasks unrelated to seed sowing, such as harvesting or spraying without seeding functionality, were omitted unless seed sowing was a core component [21], [24]. Publications lacking technical depth, experimental validation, or clear methodological descriptions were excluded to avoid ambiguous or non-reproducible findings [6], [29]. Non-peer-reviewed articles, short abstracts, patents, and non-

English publications were also excluded to maintain the quality and reliability of the reviewed literature [26].

### III. LITERATURE SURVEY

Research on automated seed sowing has evolved significantly over the past decade, driven by the need to improve agricultural productivity, reduce labor dependency, and enable precision farming. Early design-oriented studies focused on developing low-cost and mechanically simple seed sowing robots capable of replacing manual operations. Kumar and Ashok and Kumar et al. presented foundational work on automated seed sowing machines emphasizing uniform seed placement and reduced human effort. These studies demonstrated that even basic motor-driven mechanisms could significantly enhance sowing efficiency when compared to traditional methods. Similar efforts by Mohammed and Jassim explored the design and testing of robotic systems integrated with combined seeding machines, highlighting improvements in operational consistency while also pointing out challenges related to system complexity and field adaptability.

As research progressed, wireless control and embedded systems became central to seed sowing robot development. Khot et al. and Sugadev et al. introduced wireless-controlled robotic platforms using microcontrollers, enabling remote operation and improved user convenience. Jayadevan et al. further extended this approach by implementing Bluetooth-enabled Arduino-based seed sowing robots, making such systems accessible and cost-effective for small-scale farmers. These studies collectively demonstrated that wireless communication significantly enhances usability but often limits autonomy due to dependence on manual control inputs. The integration of smart agriculture concepts marked a major shift in research direction. Pradhan et al. provided an extensive overview of robotic seeding systems within smart agriculture, emphasizing sensor-based decision-making, automation, and data-driven farming practices. Lachure and Doriya proposed fog computing-based seed sowing robots, addressing latency and real-time processing challenges in IoT-enabled agricultural systems. Murugiah et al. reviewed IoT-integrated smart seeding robots and highlighted the growing importance of cloud connectivity, real-

time monitoring, and intelligent control in modern farming environments. These studies underscore the transition from isolated robotic systems to interconnected agricultural ecosystems.

Mechanical innovation in seed dispensing mechanisms has also been a key research focus. Azmi et al. [4] investigated the structural and mechanical design of agricultural robots for crop seeding, prioritizing durability and terrain adaptability. Vallikannu et al. [5] proposed a rack-and-pinion-based seed sowing robot that improved mechanical precision and control accuracy. Pradeep et al. [8] introduced a shrimp mechanism-based seed sowing robot to enhance seed placement reliability, while Ramesh et al. [11] focused on optimizing mechanical layouts for automatic seed sowing machines. These contributions demonstrate that mechanical design plays a critical role in achieving consistent sowing performance across diverse field conditions.

Recent studies have emphasized multifunctionality and sustainability in agricultural robots. Somasundaram et al. developed an automated seed sowing and watering robot using wireless sensor networks, illustrating the benefits of integrating multiple agricultural operations into a single platform. Fadhael et al. and Sai Yaswanth et al. expanded robotic capabilities to include fertigation, pesticide spraying, and solar power integration, contributing to environmentally sustainable farming solutions. Shanmugasundar et al. further demonstrated the feasibility of solar-powered autonomous seed sowing robots, highlighting energy efficiency as a critical design consideration. Autonomy, precision, and intelligent control represent the most recent and advanced research trends. Lambor et al. proposed an autonomous farming robot for precision seed sowing and targeted irrigation, showcasing improved accuracy through wireless control. Mohshin et al. introduced a closed-loop controlled autonomous seed sowing robot to enhance repeatability and precision under varying field conditions. Vision-based and data-efficient approaches have gained attention, as demonstrated by Aotake et al. and Otani et al., who employed image analysis and expert knowledge for accurate sowing position estimation in complex agricultural environments. Munnaf et al. further evaluated robot-driven site-specific seeding combined with fertilization, emphasizing agro-economic benefits and resource optimization.

Several recent studies and reviews have synthesized existing advancements while identifying open research challenges. Agrawal provided an early review of automated seed sowing machines, outlining technological trends and limitations. Murugiah et al. and Ragavendiran et al. discussed innovative design approaches and soil monitoring integration, stressing the need for scalable and farmer-friendly solutions. Vimalesh and Ramesh and Arun Praveen et al. focused on optimized and self-operated robotic designs, reflecting current efforts toward practical deployment and performance enhancement. Collectively, the literature reveals a steady progression from basic automation to intelligent, autonomous, and sustainable seed sowing robots, while also highlighting persistent challenges related to cost, adaptability, and large-scale field validation.

Table.1. Literature Summary

Category	Key Technologies	Core Contributions
Basic automated sowing	DC motors, simple automation	Reduced labor and im-proved sowing uniformity
Wireless-controlled robots	Arduino/ESP, Blue-tooth, RF	Remote operation and user-friendly control
Smart & IoT-based systems	IoT, fog/cloud computing, sensors	Data-driven and connected agriculture
Mechanical innovations	Rack–pinion, shrimp mechanism	Enhanced precision and reliability
Multifunctional platforms	Seeding, watering, fertigation, solar	Increased functionality and sustainability
Autonomous & intelligent robots	Closed-loop control, vision, AI	High precision and reduced human intervention
Economic& field evaluation	Agro-economic analysis	Validation of feasibility and efficiency
Review & sur-vey studies	Literature synthesis	Identification of trends and gaps

#### IV. IDENTIFIED RESEARCH GAPS

Despite significant progress in the development of automated and robotic seed sowing systems, a detailed analysis of existing literature reveals several unresolved technical, practical, and theoretical gaps that limit large-scale adoption and real-world effective-ness.

#### Technical Gaps

From a technical perspective, many seed sowing robots rely on open-loop or semi-autonomous control strategies, which limits their ability to adapt to dynamic field conditions such as soil heterogeneity, uneven terrain, and varying crop requirements [2], [18]. Although recent studies have explored closed-loop control, vision-based sensing, and data-efficient positioning techniques, these approaches often demand higher computational resources and complex system integration, making them less accessible for low-cost agricultural applications. Additionally, interoperability between sensing, actuation, and communication modules remains limited, leading to fragmented system designs that are difficult to scale or standardize across different farming environments

#### Practical Gaps

Practical challenges form another critical research gap. Many reported robotic seed sowing systems are validated only in laboratory settings or small experimental plots, with limited long-term field trials under real agricultural conditions. Factors such as dust, moisture, power fluctuations, and mechanical wear are often insufficiently addressed, affecting system reliability and durability. Furthermore, while multifunctional robots have been proposed, the added mechanical and control complexity in-creases maintenance requirements and operational costs, reducing their attractiveness for small and marginal farmers. The lack of farmer-centric design, including intuitive interfaces and localized adaptability, further hinders widespread adoption.

#### V. PROPOSED METHODOLOGY

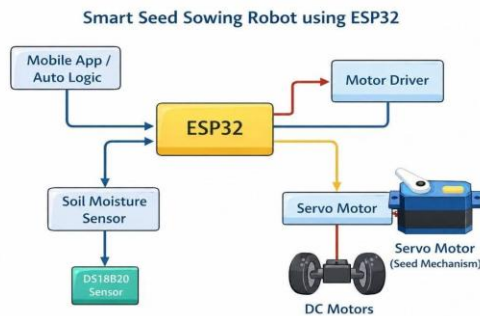
The proposed methodology aims to address the technical and practical limitations identified in existing seed sowing robotic systems by adopting a modular, cost-effective, and semi-autonomous design philosophy. The system is conceptualized to support precision seed placement, reliable field operation, and ease of use for small and medium-scale farming applications while allowing future scalability toward higher autonomy.

#### Architecture overview

The proposed seed sowing robot is designed as a compact, mobile agricultural platform capable of performing controlled seed dispensing while

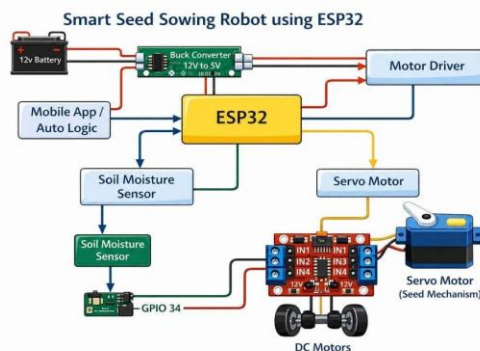
navigating agricultural fields through wireless or semi-autonomous control. The system integrates a microcontroller-based control unit with motion actuators, a seed dispensing mechanism, and wireless communication modules. Emphasis is placed on uniform seed spacing, consistent sowing depth, and reduced manual intervention, aligning with precision agriculture objectives highlighted in recent studies. The design prioritizes affordability, simplicity, and robustness to ensure suitability for real-world farming environments.

Figure.1. Architecture Diagram



The architecture of the proposed system follows a layered approach consisting of sensing, control, actuation, and communication layers. At the core lies an embedded controller responsible for processing control commands and coordinating system operations. Motion control is achieved through motor driver circuits interfaced with drive motors for navigation, while a dedicated actuator controls the seed dispensing mechanism. Wireless communication enables remote operation and monitoring via a mobile or web-based interface, supporting farmer-friendly interaction. The modular architecture allows seamless integration of additional sensors, such as soil moisture or obstacle detection units, to enhance adaptability and system intelligence.

Figure 2. Circuit Diagram



### Control Algorithms

The operational logic of the robot is governed by lightweight control algorithms focused on reliability and real-time responsiveness. Movement control algorithms regulate speed and direction based on user input or predefined motion patterns, ensuring stable navigation across field surfaces. Seed dispensing is controlled using timed or position-based actuation algorithms that synchronize seed release with robot movement to maintain uniform spacing. Provision is made for closed-loop control enhancements, where feedback from sensors can be used to dynamically adjust dispensing rates and movement parameters, addressing precision limitations observed in open-loop systems.

### Workflow Design

The workflow begins with system initialization and parameter configuration, where the user defines operational settings such as movement speed and seed spacing. Upon activation, the robot navigates the field following user commands or predefined paths while continuously coordinating movement and seed dispensing actions. Wireless commands are processed in real time, enabling on-the-fly adjustments during operation. After task completion, the system halts safely and can transmit operational data for monitoring or analysis. This structured workflow ensures repeatable, efficient, and user-controlled sowing operations while maintaining flexibility for future upgrades toward autonomous navigation and intelligent decision-making.

## VI. COMPARATIVE ANALYSIS WITH EXISTING SYSTEM

The comparative analysis highlights strengths, limitations, and distinct contributions of representative robotic solutions in terms of automation level, control strategy, mechanical design, functionality, and practical applicability.

Table 2. Automation and Control Strategy

System	Automation Level	Control Type	Key Strength	Limitation
Kumar &	Semi-automated	Manual + Basic Control	Simple and	Low adaptability

Ashok [1]			cost-effective	
Khot et al. [2]	Semi-automated	Wireless remote	Enhanced convenience	Limited autonomy
Jayadevan et al. [15]	Semi-automated	Bluetooth control	Easy operation	Short range control
Lambor et al. [10]	Autonomous	Wireless + Predefined patterns	Higher precision	Complexity & cost
Mohshin et al. [18]	Autonomous	Closed-loop control	High repeatability	Computational demand
Proposed System	Semi-autonomous (scalable)	Modular control with optional closed-loop	Balanced precision & cost	Future full autonomy needed

Existing seed sowing robots vary widely in automation. Early systems primarily rely on manual or wireless remote control, offering convenience but limited adaptability to field variations. Advanced systems such as those by Lambor et al. and Mohshin et al. incorporate autonomous behavior and closed-loop feedback, resulting in better seed placement precision. However, they demand high computation, sophisticated sensors, and system complexity, increasing cost and maintenance efforts. The proposed system strikes a middle ground by allowing modular control that can operate as remote-assisted or evolve toward full autonomy with sensor feedback integration.

Table 3. Mechanical Design and Seed Dispensing Mechanism

Design Approach	Representative Works	Key Feature	Practical Strength
Basic Mechanisms	[1], [2], [29]	Simpler designs with DC motors	Low cost and easy fabrication

Enhanced Precision	[4], [5], [8], [11]	Rack-pinion / shrimp / optimized mechanisms	Improved seed placement accuracy
Multifunctional Platforms	[7], [13], [14]	Combining sowing with watering/spraying	Increased utility
Proposed Design	Modular mechanism	Custom dispensing synchronized with motion	Balance of reliability & simplicity

Early studies focus on straightforward seed dispensing using DC or stepper motors supporting basic accuracy and uniformity ([1], [2], [29]). Advances by Azmi et al. [4], Vallikannu et al. [5], and Pradeep et al. [8] demonstrate redesigned mechanical linkages (rack-pinion, shrimp mechanism) that improve seed drop precision. Multifunctional robots such as those by Somasundaram et al. [7] and Fadhaeel et al. [13] incorporate additional operations (watering, fertigation), increasing agricultural utility but also adding mechanical complexity and weight. The proposed design focuses on a modular, reliable seed dispensing mechanism synchronized with navigation, offering improved performance over basic robots while avoiding excessive complexity found in multifunctional platforms.

Table 4. Communication and Sensor Integration

System Category	Representative Works	Communication/Sensing	Strength	Weakness
Wireless control focus	[2], [15], [20]	Bluetooth / RF	Simple remote command	Limited extended sensing
IoT & smart integration	[3], [9], [12], [22]	IoT, fog/cloud	Connected agriculture insights	Dependency on networks
Vision & AI-	[19], [24]	Image analysis	Precision decisions	High computational load

based				
Proposed Integration	Modular wire-less + sensor inputs	Sensor-ready architecture	Scalable & adaptable	Needs implementation

Control and communication evolution is evident across the literature. Many early systems emphasize wireless remote controls to improve usability without complex sensing. More recent research emphasizes IoT connectivity and data integration, as shown by Pradhan et al., Murugiah et al., and Lachure & Doriya enabling real-time monitoring and remote data analytics. Vision-based and AI-driven approaches by Aotake et al. and Otani et al. push precision further with adaptive decision-making, but at a cost of heavy computation and sensor complexity, not yet validated for low-cost agricultural deployment. In comparison, the proposed system provides a flexible architecture that supports basic wireless control with provision to incorporate advanced sensors as needed, facilitating a scalable path toward smart agriculture without forcing immediate complexity.

Table 5. Sustainability, Power, and Practical Deployment

Feature	Key Works	Strength	Limitation
Sustainable power	[14], [21]	Solar energy	Environmental progress
Economic & field evaluation	[23], [28]	Cost-benefit insights	Real-world validation

Proposed System	Field ready & expandable	Balanced cost & performance	Requires extensive field trials
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Sustainability and real-world applicability remain underexplored in many studies. Solar-powered robots by Sai Yaswanth et al. [14] and Shanmugasundar et al. [21] champion environmentally friendly operation, but susceptibility to weather and energy inconsistency persists. Works by Vahdanjoo et al. [23] and Munnaf et al. [28] provide valuable economic and operational assessments, highlighting the importance of cost-benefit analysis and practical performance validation in real agricultural contexts. The proposed

system incorporates energy-efficient components and readiness for field deployment, but comprehensive field evaluations across diverse terrains are needed to confirm reliability and adoption feasibility.

Table 6. Summary of Comparative Insights

Evaluation Criteria	Literature Status	Proposed System Position
Autonomy	Limited to semi-automated and isolated autonomous systems	Scalable toward autonomy with modular control
Precision	Improved but dependent on advanced sensing	Balanced precision with option for closed-loop control
Mechanical robustness	Varies widely with design complexity	Reliable and adaptable with moderate complexity
Usability	Often lacks farmer-friendly interfaces	Emphasis on wireless and intuitive interaction
Sustainability	Some energy-efficient efforts	Designed for energy efficiency; needs field validation
Real-world validation	Minimal field deployment	Planned systematic field trials

In summary, while many existing seed sowing robots demonstrate valuable contributions—ranging from simple automated mechanisms to IoT-integrated and autonomous platforms—significant gaps remain in achieving cost-effective, robust, scalable, and field-validated solutions. The proposed methodology seeks to address these gaps by balancing precision, practicality, modular design, and future scalability, positioning it as a promising direction for next-generation agricultural robotics.

## VII. ADVANTAGES AND APPLICATIONS

The proposed seed sowing robotic system offers notable advantages in terms of precision, efficiency, and practicality. Controlled seed dispensing ensures

uniform spacing and consistent sowing depth, which improves germination rates and crop uniformity while minimizing seed wastage. Automation significantly reduces labor dependency and operational time, addressing workforce shortages commonly reported in agricultural sectors. The use of wireless and modular control enhances ease of operation, allowing farmers to manage sowing tasks with minimal technical expertise. Additionally, the system is designed to be cost-effective and scalable, enabling future integration of sensors, closed-loop control, or renewable energy sources without major structural modifications

In terms of applications, the system is well suited for small and medium-scale farming, where affordability and adaptability are critical factors. It supports precision agriculture practices by enabling accurate and repeatable sowing operations, which are essential for yield optimization and efficient resource utilization. The robot can also be deployed in smart farming environments that leverage IoT-based monitoring and data-driven decision-. Furthermore, it serves as a valuable platform for agricultural research, technology validation, and educational purposes, contributing to the development and dissemination of advanced agricultural robotics solutions

## VIII. CONCLUSION

This review presented a comprehensive analysis of automated and robotic seed sowing systems, highlighting their evolution from basic mechanized solutions to intelligent, connected, and semi-autonomous agricultural platforms. The literature demonstrates that seed sowing robots significantly enhance sowing precision, reduce labor dependency, and support efficient resource utilization, making them an essential component of modern precision agriculture. Advances in mechanical design, wireless communication, IoT integration, and intelligent control have collectively contributed to improved system performance and usability. However, variations in design complexity, cost, and validation approaches across studies indicate the absence of standardized frameworks and benchmarks for evaluating seed sowing robotic systems

Despite notable progress, several challenges remain unresolved, including limited real-world field validation, adaptability to diverse soil and terrain conditions, and the need for farmer-centric, affordable

solutions. Future research should focus on developing scalable architectures that balance autonomy and cost, integrating agronomic intelligence with adaptive control algorithms, and establishing unified evaluation metrics for performance and sustainability. Addressing these challenges will be critical for transitioning seed sowing robots from experimental prototypes to widely adopted agricultural tools that support sustainable and intelligent farming practices.

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