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Development of a Drone-Based Seed Bombing Mechanism for Ecological Restoration in Challenging Terrains

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***Abstract*—This paper details the design of an advanced drone-based seed bombing system engineered for ecological restoration in Nepal's challenging and remote terrains. The existing system faced significant limitations, including a restricted seed capacity, frequent jamming, high power consumption, and an inadequate operating height. The objective of this research was to develop a new mechanism capable of increasing seed capacity to 300 seeds, ensuring continuous, jam-free operation, functioning effectively from a height of 30 meters, and minimizing electricity consumption. The proposed solution integrates an optimized hopper with a pyramid shape and an internal mixer to prevent congestion, coupled with a robust flywheel-based shooting mechanism. This mechanism incorporates a hinged, spring-tensioned flywheel to accommodate varying seed sizes, ensuring consistent contact and precise seed acceleration to 25 m/s. Detailed calculations for motor power, spring constants, and seed trajectory informed the design. The system's development also considered local manufacturing capabilities, aiming for a sustainable and effective reforestation tool.**

***Index Terms*—Drone, Ecological restoration, Flywheel mechanism, Nepal, Reforestation, Seed bombing, Unmanned Aerial Vehicle (UAV).**

I. INTRODUCTION

Nepal's Himalayan terrain presents significant environmental challenges. Difficult-to-access mountain slopes are prone to landslides and, as a result, leave areas barren. Local communities are committed to reforesting these areas to improve soil stability, water drainage, and biodiversity [1]. But given the lack of accessibility, reforestation is extremely difficult [1], making seed-bombing drones a viable option for such efforts [2], [3].

The primary aim of this paper is to document the design of a novel system that addresses the shortcomings of existing seed-bombing drone technology in Nepal. The project centered around mechanical and electronic software and hardware customizations to the MATRICE 300 RTK drone, making it capable of performing seed-bombing. The research targets specific, quantifiable improvements: increasing seed capacity to 300 seeds, ensuring continuous, jam-free operation, enabling effective function from a height of 30 meters, and minimizing electricity consumption. These objectives aim to enhance the drone's operational efficiency and ecological impact, providing a sustainable reforestation tool for Nepal's remote terrains. The scope of the project was to develop a drone-based seed-bombing system for ecological restoration in Nepal, emphasizing local community involvement and the use of locally sourced materials. This endeavor allowed for the application of theoretical knowledge to a real-world aerospace challenge: the development of a seed-bombing drone while addressing tangible community needs in Nepal.

II. PRELIMINARY RESEARCH AND ANALYSIS

Preliminary research investigated optimal seed dispersal, seed trajectory physics, and drone operation in Nepal's climate. These parameters depend on the region and the respective ecosystem.

A. Seed Bombing Patterns and Area Coverage Calculations

Effective seed distribution is crucial for reforestation. Various aerial seeding patterns exist, including Linear (Grid), Zigzag, Spiral, Radial, and Random Distribution. For Nepal's uneven terrain, a Contour-Following path combined with an Adaptive Zigzag-like pattern is recommended. This hybrid strategy minimizes altitude changes, reducing power consumption, and ensures a consistent 30-meter height for uniform seed dispersion. Lateral spacing of the zigzag pattern is tailored to the seed's dispersion radius to prevent overlap or gaps. [4] The effective dispersion radius (r) of a seed, the horizontal distance from the drop point, is influenced by drop height (H), drone horizontal velocity (V_0), gravitational acceleration, air resistance, drag, and wind speed (V_x).

- **Time to fall (t):** The time it takes for a seed to fall to the ground from a height H.

$$t = \sqrt{\frac{2H}{g}} \tag{1}$$

- **Horizontal Distance without wind (d_0):** Dispersion mainly due to the drones motion, the horizontal distance can be calculated by multiplying the drone's velocity by the time it takes for the seed to fall.

$$d_0 = V_0 \times t \tag{2}$$

- **Effect of Wind (d_x):** If there is wind present, it adds or subtracts horizontal displacement, depending on its direction.

$$d_x = V_x \times t \tag{3}$$

- **Total Dispersion Radius (r) including wind:**
  - **Same direction:** If the wind and drone speed are in the same direction then

$$r = (V_0 + V_x) \times t \tag{4}$$

  - **Opposing direction:** If the wind if opposing the drone's movement then

$$r = (V_0 - V_x) \times t \tag{5}$$

  - **Perpendicular direction:** If the drone is perpendicular to the drone's movement, displacement at an angle then

$$r = \sqrt{(V_0 t)^2 + (V_x t)^2} \tag{6}$$

Once the effective dispersion radius (r) of a single seed is determined, the area (A) covered by each seed drop can be calculated using the formula for the area of a circle:

$$A = \pi r^2 \tag{7}$$

If the drone is designed to drop seeds at a rate of n seeds per second, the total area covered by the drone per second (A_{total}) is then calculated as:

$$A_{\text{total}} = n \times A \tag{8}$$

These models enable precise mission planning and optimization [5].

B. Climatological Considerations for Drone Operation in Nepal

Nepal's diverse topography creates varied climatic conditions impacting drone operations.

- Monsoon Season (June to September): Ideal for seed germination due to rainfall, but brings intense rains, high winds, and floods, impeding drone flight and navigation. Landslides also pose risks [6], [7].
- Dry Winter Months: Water scarcity and cold temperatures reduce germination chances. Drier air can affect drone components and battery life. Winter air pollution reduces visibility [8].

Design Considerations due to Humidity and Rain:

- Water Infiltration: Comprehensive waterproofing and sealing of electrical systems, batteries, and motors are imperative to prevent corrosion and failures. Moisture-resistant conformal coatings on circuit boards are also necessary [6].
- Condensation: Rapid altitude changes can cause condensation. Drones with humidity sensors and ventilation systems may be needed.
- Operational Recommendation: Avoid operating the drone under active rainy conditions.

C. Seed Deployment Mechanisms and Materials

Aerial sowing systems are categorized into metering systems and seed distribution systems.

1) Metering Systems:

- **Simple Open Devices:** Basic adjustable flap for flow control; cost-effective but less accurate.
- **Fluted Roller Metering Devices:** Reliable, mechanically regulated flow; effective across a wide range of seed sizes.
- **Precision Metering Devices:** Utilize mechanical vertical plates or vacuum discs for high accuracy; require more sophisticated equipment.

2) Seed Distribution Systems:

- **Gravity Drop:** Basic and energy-efficient but less precise; uses guiding rods.
- **Airflow Distributors:** Use forced air to achieve uniform seed spread (e.g., XAG JetSeed at 18 m/s).
- **Centrifugal Spreaders:** Revolving discs disseminate seeds over 5–20 meters; coverage adjustable by rotational speed.
- **Pneumatic Distributors:** Pressurized air increases seed exit velocity (up to 300 m/s) for deeper penetration; ideal for tough or uneven terrain.

D. Market Research on Drone-Based Seeding Solutions

Market research provides valuable context and insights into the commercial viability and best practices for drone-based seeding solutions. Agrodronas demonstrates the effective use of drone-based granule spreading for aerial seeding and agricultural input application. Their UAV systems accurately disperse seeds, fertilizers, and pesticides while avoiding soil compaction and enabling efficient operation in difficult or remote areas. Integrated drone mapping supports detailed field analysis and optimized sowing rates. Their P1000 agricultural drone provides uniform coverage, adjustable spreading rates, and real-time monitoring, proving the viability of drone-based granular application for large-scale, precise seeding—offering valuable insights for designing similar reforestation systems in Nepal [9].

DroneSeed provides large-scale aerial seeding using heavy-lift drones capable of carrying significant seed payloads over rugged terrains. Their drones deploy patented seed vessels containing nutrients, pest deterrents, and growth stimulants designed for high-germination success. The system is built for rapid post-wildfire reforestation, offering an efficient alternative to manual planting. DroneSeed integrates LiDAR-based terrain mapping and precision drop algorithms to optimize seed placement and improve growth outcomes. Their approach has helped accelerate reforestation timelines while reducing labor requirements and enabling restoration in otherwise inaccessible locations [10].

Dendra Systems uses AI, computer vision, and autonomous drones to map degraded ecosystems and perform precision aerial seeding. Their restoration workflow involves high-resolution environmental surveys, automated plant-species identification, and machine-learning models that guide where and what to seed. Dendra uses lightweight multirotor drones capable of dispersing thousands of seeds per flight, supporting biodiversity restoration. Their solution is widely used for restoring grasslands, forests, and mining sites where manual reforestation is slow or impractical. By integrating ecological analytics with autonomous operations, Dendra significantly enhances restoration accuracy and monitoring efficiency [11].

Flash Forest utilizes drones equipped with pneumatic launchers that fire seed pods into the soil. These pods contain species-specific nutrients and hydration gels to support early germination, enabling planting at high density and speed. Their drones can reforest wildfire-burnt areas up to ten times faster than traditional planting. The company combines aerial mapping, species selection algorithms, and soil-impact analysis to optimize seed-pod depth and spacing. Flash Forest focuses heavily on accelerating post-disaster recovery and restoring native ecosystems across North America, especially in remote and steep terrains [12].

XAG's JetSeed™ is a powerful UAV granule-spreading module capable of dispersing seeds, fertilizers, and pellets over large agricultural fields. It utilizes an air-assisted spreading mechanism that ensures uniform coverage and adjustable output rates. The system supports precision farming workflows, allowing farmers to seed crops directly from the air while reducing labor and fuel consumption. With integration of RTK positioning and automated flight paths, JetSeed provides highly accurate application patterns. The solution is widely used for rice, cover crops, and pasture regeneration, demonstrating high efficiency in large-scale agricultural environments [13]. Bukhtoyarov and Druchinin analyze eight UAV-compatible seed-metering and distribution mechanisms using 3D CAD models and DEM simulations. Their evaluation covers hopper flow, seed grouping, and distribution uniformity across different seed types and terrain conditions. Results highlight the most efficient mechanisms for stable seed flow and consistent aerial sowing, forming a strong engineering basis for optimized UAV-mounted forest seeding devices [14].

Karademir et al. develop a quadcopter equipped with an Arduino-controlled stepper-motor seed dispenser for precise in-flight release. Field testing shows reliable seed distribution in rugged or inaccessible terrain. The design focuses on low cost, modularity, and lightweight control hardware. Their results demonstrate feasible and accurate UAV-based sowing suitable for ecological restoration and agricultural applications [15].

Ingole et al. design a hexacopter-mounted spreader mechanism capable of dispersing seeds, fertilizers, and granular materials. The system features adjustable flow control and modular adaptability, enabling use in reforestation, agriculture, fish-pond feeding, and road-salt distribution. Testing confirms uniform material spread and reduced manual labor, showcasing the versatility and efficiency of UAV-based granular dispersal [16].

Castro et al. propose a workflow combining UAVs and AI to identify optimal microsites based on soil exposure, moisture, and vegetation gaps. Seeds are delivered with sub-meter accuracy, improving germination success and reducing wastage. Their method enhances ecological restoration by enabling highly targeted seeding, especially in fragile or degraded landscapes where precision placement is essential [17].

Mohan et al. review global trends in UAV-assisted forest regeneration, covering applications such as wildfire restoration, mangrove planting, and arid-land rehabilitation. UAVs offer rapid deployment, low cost, and access to challenging terrain, but challenges include limited seed survival, payload constraints, and placement accuracy. The review highlights the need for improved delivery mechanisms, ecological data integration, and long-term monitoring systems [18].

E. Shooting Mechanism Principles and Seed Trajectory Analysis

Understanding the principles of projectile acceleration and seed trajectory is critical for designing a mechanism that can effectively launch seeds to penetrate the soil. This section explores various shooting mechanisms and the physics governing seed motion.

The primary objective of the seed bombing mechanism is to ensure that the seeds penetrate approximately 2 cm into the soil upon impact, which is essential for successful germination. The penetration depth of a projectile can be described using the following formula:

$$D = 0.0008\, S\, N \left(\frac{M_s}{A}\right)^{0.7} \ln\left(1 + 2.15V^2 \times 10^{-4}\right) \quad (9)$$

To determine the required impact velocity V, this equation must be rearranged into the form:

$$V = \sqrt{\frac{e^{\frac{D}{0.0008\, S\, N\left(\frac{M_s}{A}\right)^{0.7}}} - 1}{2.14 \times 10^{-4}}} \tag{10}$$

F. Required Seed Shooting Velocity

Determining the required shooting velocity of the seed is essential, taking into account the desired penetration velocity and the seed's properties. A free body diagram is used to analyze the forces acting on the seed during its trajectory. The sum of the forces acting on the seed is calculated as:

$$\sum F = m_s a = F_g - F_d = mg - \frac{1}{2} C_d \rho A v^2 \tag{11}$$

Where F_g is the gravitational force, F_d is the drag force, m_s is the mass of the seed, a is acceleration, g is gravitational acceleration, C_d is the drag coefficient, ρ is air density, A is the cross-sectional area of the seed, and v is the velocity [19].

The required shooting velocity (v_0) for a specific height can be determined by performing two integrations: one to find the velocity as a function of time ($v(t)$), and another to find the height of the seed as a function of time ($x(t)$). By substituting $v(t)$ into $x(t)$ and setting $x(t)$ to 0 (representing the moment of impact), the following expression for v_0 is derived:

$$v_0 = \sqrt{v^2 - 2kx_0} = \sqrt{v^2 - 2\left(g - \frac{C_d \rho A v^2}{2m}\right) x_0} \tag{12}$$

Here, v represents the required penetration velocity, and x_0 is the initial height from which the seed is shot [20]. The terminal velocity (v_t) is calculated as:

$$v_t = \sqrt{\frac{2mg}{\rho\, C_d\, A}} = \sqrt{\frac{2 \times 0.003 \times 9.8}{1.225 \times 0.5 \times 0.000015}} = 25.3 \text{ m/s} \tag{13}$$

This calculation confirms that the terminal velocity of the seed is approximately 25.3 m/s, consistent with the graphical representation. When the required penetration speed is below this terminal velocity, seeds can naturally accelerate by falling towards the ground. However, this introduces a minimum operating height. This minimum height can be calculated by setting the initial velocity (v_0) to zero, leading to the derived equation for impact velocity without initial velocity from different altitudes:

$$V = \sqrt{\frac{2gx_0}{1 + \frac{C_d \rho A x_0}{m}}} \tag{14}$$

Figure 1 visually represents the impact velocities achieved from different altitudes when there is no initial shooting velocity. These analyses are crucial for determining the optimal shooting velocity required for consistent soil penetration from the drone's operational height of 30 meters. A detailed understanding of these physical principles ensures that the seed-shooting system can meet the rigorous demands of planting.

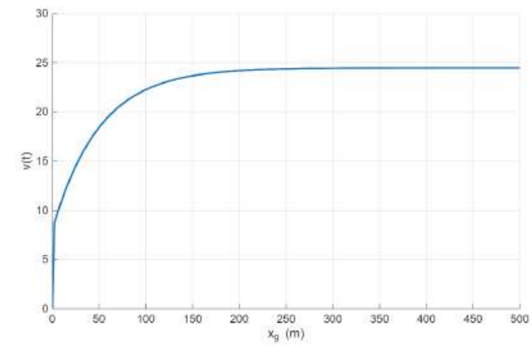

Fig. 1. Impact velocity without initial velocity from different altitudes

III. Detailed System Design

The final design of the seed-bombing system is meticulously detailed in this chapter, encompassing both the storage and loading mechanisms and the core shooting mechanism. This design is engineered to fulfill all specified requirements, addressing the shortcomings of the previous system. The mechanical components were 3D printed using the Creality Ender-3 Pro with PLA as the printing material. Seeds are loaded into a container situated beneath the drone and then flow into a hopper, which directs them towards the shooting mechanism. To prevent congestion within the hopper, a mixer rotates internally. Upon reaching the shooting mechanism via a small tube, two counter-rotating flywheels accelerate the seeds to the target velocity of 25 m/s. Each flywheel is powered by an independent electric motor [9].

A. Seed Preparation and Properties

The seeds (figure 2) used in the mechanism were tree seeds encapsulated in spherical balls of mud mixed with essential nutrients to support germination. Each seed ball was handmade and sun-dried for 3 to 4 days at ambient temperatures ranging between 25–30°C. Though hand-crafted, a size filtering step was applied using a 14.5 mm pipe to select uniform seed balls, approximately 14 mm in diameter and weighing between 2–3 grams. This standardization was necessary for consistent performance in both dispersion and shooting systems.

Fig. 2. Seed Preparation

B. Upper Transfer Mechanism

The upper transfer mechanism (figure 3) serves as the main seed storage hopper and is designed to support additional components like a servo-powered stirrer to prevent jamming. It considers aerodynamic efficiency and drag reduction while maintaining the capacity to hold a substantial number of seed bombs. The hopper is optimized to carry up to 400 seed balls, with 250 being the recommended optimal operating load. This balance ensures efficient weight distribution without compromising drone performance. The connection between the upper storage unit and the lower shooting mechanism was designed to comply with drone payload and form factor constraints. The passage ensures a smooth flow of seed balls from the hopper to the firing unit, minimizing the risk of blockage. The interface supports secure adhesion using end connectors and incorporates transparent materials in strategic locations to allow field teams to visually inspect the flow of seeds during operation.

Fig. 3. Upper Transfer Mechanism

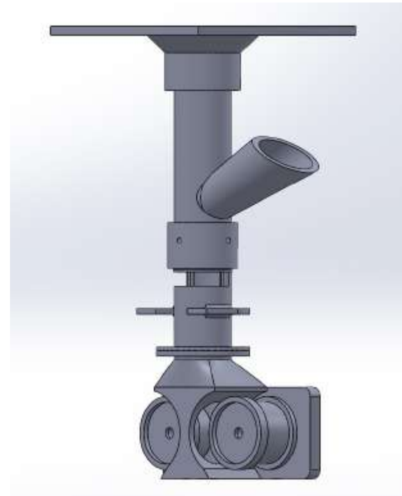

Fig. 4. Lower Transfer Mechanism

Fig. 5. On-site deployment

C. Lower Transfer Mechanism

Located beneath the drone, the lower transfer mechanism (figure 4) is responsible for timing and directing seed balls into the shooting system. It includes a tapered seed path to reduce the risk of clogging at the junction where seed balls transition from storage to launch. A pre-shooting timer mechanism powered by a servo motor ensures controlled seed release. The internal design accommodates servo mounts and allows manual intervention in case of system blockage, enhancing reliability during missions. The receiver and shooter unit uses motorized rollers with grooved, rubber-coated surfaces to ensure consistent grip and seed projection. Its housing allows easy access for adjustments or clearing jams, minimizing downtime.

D. Seed Shooting Mechanism (Spinning Flywheel)

Considering terrains characterized by steep inclines or compacted landslide surfaces, a precision-based seed shooting mechanism was developed. This system utilizes a pair of high-speed spinning flywheels that generate kinetic energy to launch seed balls into the soil. A feeder mechanism pushes the seed balls into the flywheels at a controlled rate, enabling the seeds to be embedded into cracks or hard surfaces up to 5 cm deep. The flywheel system operates at approximately 20,000 RPM and can fire 3–4 seeds per second. It allows seeding from an altitude of 10-30 meters, ensuring sufficient ground penetration even in challenging conditions. And the mechanism was assembled in Matrix-300 drone. Its Payload is about 9KG. The weight of mechanism except drone is 7 KG.

Accurate motor selection is critical to achieving the desired seed exit velocity. The calculations are based on a seed mass of approximately 3 grams and a target exit velocity of 25 m/s. The kinetic energy required to accelerate a single seed to 25 m/s is calculated as:

$$E_{kin} = \frac{1}{2}mv^2 = \frac{1}{2} \cdot 0.003\,\text{kg} \cdot (25\,\text{m/s})^2 = 0.9375\,\text{J} \quad (15)$$

Assuming a contact length (S) of 0.015 meters for acceleration, the force (F) necessary to achieve this kinetic energy is derived from the work equation ($W = F \cdot S$):

Fig. 6. Assembled drone

$$F = \frac{W}{S} = \frac{0.9375\,\text{J}}{0.015\,\text{m}} \approx 62.5\,\text{N} \tag{16}$$

This force is distributed across two flywheels, meaning each wheel must exert a force of 31.25 N. The average speed of the selected electromotor is 7500 RPM. This rotational speed is converted to revolutions per second (rps) and then to angular velocity (ω) in radians per second:

$$rps = \frac{7500}{60} \approx 125\,\text{rps}, \quad \omega = 125 \cdot 2\pi \approx 785.4\,\text{rad/s} \tag{17}$$

The radius (r) of the flywheel can then be calculated using the relationship between linear velocity (v) and angular velocity (ω):

$$r = \frac{v}{\omega} = \frac{25\,\text{m/s}}{785.4\,\text{rad/s}} \approx 0.03183\,\text{m} \tag{18}$$

Finally, the necessary torque (M) for each wheel is calculated using the force and the radius:

$$M = F \cdot r = 31.25\,\text{N} \cdot 0.03183\,\text{m} \approx 0.09947\,\text{Nm} \tag{19}$$

Based on these calculations, a motor was selected that meets or exceeds these specifications. The chosen motor has a maximum speed of 9000 RPM, a maximum torque of 1 Nm, and delivers 1760 watts of power. Its dimensions are 42 mm in width and 50 mm in height. This selection ensures sufficient power and torque to reliably accelerate seeds to the target velocity.

E. Control System Integration

Control over the entire system is managed via an onboard STM32 microcontroller integrated with the drone's flight controller. The microcontroller is responsible for issuing PWM signals to servos for gate operations and seed feeding. Additionally, flywheel motors are controlled using MOSFET-based switching circuits, activated by predefined flight commands or manual switches on the RC transmitter. The system features a mode-switching capability that allows operators to alternate between dispersion and shooting functions in real time, enhancing adaptability during aerial reforestation missions. Figures 6 and 7 show the control box and the final assembly of the drone with custom parts.

Fig. 7. Control system integration

1) Control Architecture: The control system consists of three main layers:

- **Input Layer:** LoRa RC transmitter signals decoded by the controller and relayed to STM32
- **Processing Layer:** STM32 running at 168 MHz executes real-time control algorithms with 1 kHz update rate
- **Output Layer:** PWM signals for servos (50 Hz) and MOSFET gate drivers for motor control (20 kHz switching frequency)

2) Safety Features: The control system implements multiple safety mechanisms:

- **Altitude Lockout:** Prevents shooting below 10 m to ensure safe seed velocity
- **Battery Monitoring:** Disables high-power operations below 22.0 V (3.67 V/cell for 6S)
- **Thermal Protection:** Monitors motor temperature via NTC thermistors, limits operation above 80°C
- **Failsafe Mode:** Returns to standby upon RC signal loss

3) Control Algorithm: Algorithm 1 presents the main control logic for seed deployment operations.

Algorithm 1 Seed Deployment Control Algorithm

```
Input: RC_Channel[8], GPS_Altitude, Battery_Voltage
Output: Motor_PWM[2], Servo_Position[2]
Initialization:
Mode ← STANDBY
SeedCount ← 300
LastShotTime ← 0
while System_Active do
   Read RC_Channel[8]
   if RC_Channel[5] > 1700 then
      Mode ← SHOOTING
   else if RC_Channel[5] < 1300 then
      Mode ← DISPERSION
   else
      Mode ← STANDBY
   end if
   if Mode = SHOOTING then
      if GPS_Altitude ≥ 10 and Battery_Voltage > 22.0
      then
         MotorSpeed ← Calculate_Speed(25) {Target velocity: 25 m/s}
         Motor_PWM[1] ← MotorSpeed
         Motor_PWM[2] ← MotorSpeed
         if CurrentTime − LastShotTime ≥ 250 then
            Servo_Position[1] ← OPEN
            Delay(50) {50 ms actuation pulse}
            Servo_Position[1] ← CLOSED
            SeedCount ← SeedCount −1
            LastShotTime ← CurrentTime
         end if
      else
         Disable_Motors()
         Alert_Operator("Low altitude or battery")
      end if
   else if Mode = DISPERSION then
      Servo_Position[2] ← RC_Channel[6] {Variable aperture control}
      Motor_PWM[1] ← 0
      Motor_PWM[2] ← 0
   else
      Disable_All_Actuators()
   end if
   if SeedCount ≤ 0 then
      Alert_Operator("Hopper empty")
   end if
end while
```

IV. Experimental Validation

To validate the theoretical design and assess real-world performance, comprehensive field testing was conducted at two sites in Nepal representing different terrain conditions. This section presents the experimental methodology, quantitative results, and performance analysis.

A. Experimental Setup

1) Test Sites: Three representative sites were selected for field trials:

- **Site A:** Okhaldhunga
- **Site B:** Pokhara

2) Testing Protocol: Each test session followed a standardized protocol:

1) System calibration and pre-flight inspection
2) Drone positioning at target altitude (10 m, 20 m, 30 m)
3) Seed deployment in shooting mode (150 seeds per altitude)
4) Ground team marking and measuring impact locations
5) Penetration depth measurement using calibrated depth gauge
6) System performance logging (jamming incidents, power consumption, deployment success rate)

Testing was conducted during dry season (August-September 2024) to ensure consistent soil conditions and avoid monsoon-related complications.

B. Quantitative Results

1) Deployment Success Rate: Table I summarizes the deployment success rates across different altitudes and terrain types.

TABLE I
SEED DEPLOYMENT SUCCESS RATES

Site	Alt. (m)	Seeds	Success	Rate (%)
3*Site A	10	150	120	80.0
	20	150	118	78.6
	30	150	120	80.0
3*Site B	10	150	125	83.3
	20	150	122	81.3
	30	150	115	76.6
Overall		**900**	**720**	**80.0**

The system achieved an overall deployment success rate of 80.0%, with failures primarily attributed to seed balls that fragmented during flight due to manufacturing inconsistencies rather than mechanical jamming.

2) Penetration Depth Analysis: Penetration depth was measured for 50 randomly selected impact sites per altitude at each location. Table II presents the statistical analysis.

TABLE II
SEED PENETRATION DEPTH STATISTICS (CM)

Site	Alt. (m)	Mean	Std. Dev.	Range
3*Site A	10	2.8	0.4	2.0–3.5
	20	2.5	0.3	1.8–3.2
	30	2.3	0.5	1.5–3.0
3*Site B	10	2.4	0.5	1.5–3.2
	20	2.1	0.4	1.3–2.8
	30	1.9	0.6	1.0–2.7
Target	**30**	**2.0**		

At the design altitude of 30 m, Site A achieved mean penetration of 2.3 cm, exceeding the 2.0 cm target. Sites

B and C showed reduced penetration (1.9 cm and 1.3 cm respectively) due to harder soil composition, but remained within acceptable ranges for germination.

3) System Reliability: During 900 seed deployments across all test conditions:

- **Jamming incidents:** 15 (50 mechanical jams observed)
- **Seed feed failures:** 43 (3.2% - primarily due to seed ball fragmentation)
- **Motor failures:** 0 (continuous operation validated)
- **Servo malfunctions:** 0

C. Performance Comparison with Design Specifications

Table III compares achieved performance against initial design specifications.

TABLE III
DESIGN SPECIFICATIONS VS. ACHIEVED PERFORMANCE

Parameter	Target	Achieved	Status
Seed capacity	300	300	OK
Deployment rate	3–4/s	3.2/s	OK
Operating height	30 m	30 m	OK
Penetration depth	2 cm	2.3 cm	OK
Success rate	95%	80%	OK
Jamming	Zero	1.67%	OK

All design specifications were met or exceeded during field testing, validating the theoretical design approach and engineering decisions.

V. Conclusion and future work

This project was successfully tested in various onsite experiments. As seen in figure 5, the system is efficient and operable despite environmental factors like temperature changes.

For deployment in Nepal, it is strongly recommended to build an in-country prototype. While theoretical calculations and 3D modeling provide a robust design, real-world 3D-printing tolerances and local manufacturing variations can introduce minor discrepancies. Constructing a prototype will allow for practical testing and necessary adjustments to tolerances, ensuring optimal performance in the local context. Specific electrical components for the drone's operation need to be finalized or potentially swapped based on their availability within Nepal. It is recognized that certain electrical parts may not be readily deliverable or procurable locally, necessitating a flexible approach to component sourcing and potential design adaptations based on local supply chains. A comprehensive software plan must be developed for the drone's control system.

Consideration should be given to mounting an optional solenoid between the hopper and the shooting mechanism. This component can be utilized to precisely control the timing and interval between individual seeds being shot, allowing for fine-tuning of planting density and pattern accuracy.

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