

High-tech Advanced Roadside Vehicle Breakdown and Accidental Service System

Prof. Ayaz Shaikh¹, Khushboo Lanjewar², Sahili Bhowate³, Madhura Lakhote⁴,
Achal Kewat⁵, Diksha Tembhurne⁶, Sharwari Somkuwar⁷, Nisha Meshram⁸

Assistant Professor, Department of Computer Science & Engineering¹

Students, B-TECH Graduate (IV year), Department of Computer Science & Engineering^{2,3,4,5,6,7,8}

Nagpur Institute of Technology, Nagpur, Maharashtra, India

Abstract: *The High-tech Advanced Roadside Vehicle Breakdown and Accidental Service System is an innovative solution designed to enhance the efficiency and effectiveness of roadside assistance and accident response services. High-tech advanced Roadside Vehicle Breakdown And Accidental service system Application is a mobile app designed to provide quick and efficient roadside assistance to users experiencing vehicle breakdowns. The application will be built using Android Studio with Java as the primary programming language, and it will leverage Firebase Database for real-time data storage and retrieval. Additionally, a user-friendly mobile application allows users to request assistance, track progress, and access relevant information. With a built-in data analytic module, the system collects and analyzes data to optimize performance. the High-tech Advanced Roadside Vehicle Breakdown and Accidental Service System aims to revolutionize the industry by providing faster, more efficient, and customer -centric service.*

Keywords: user, vehicle, registration, login, etc

REFERENCES

- [1]. According to Shuiping Wei, Bangyan Ye, and Zhiguang Fu's 2007 study, "Research on GPS Positioning Information Transfer Based on Wireless Network, 28(6): 589-592,"
- [2]. Mark L.Murphy, (2008) "The Busy Coder's Guide to Android Development," United States of America, Commons Ware, and LLC.
- [3]. M.Murphy,(2010) Beginning Android 2, A press
- [4]. R.Meier,(2010)Professional ndroid 2 Application Development,Wiley.
- [5]. J.Pérez,V.Milan's, and E.Onieva, 2011 "Cascade Architecture for Lateral Control in Autonomous Vehicles," IEEE Tr.on ITS vol. 12, pp. 73-82.
- [6]. M. H. Lee, K. Lee, S, H. G. Park, Y. C. Cha, J. D. Kim, B. Kim, et al., 2012 "Lateral Controller Design for an Unmanned Vehicle via Kalman Filtering," International Journal of Automotive Technology, vol. 13, pp. 801-807.
- [7]. Continuous-Curvature Bounded Path Planning Using Parametric Splines," by M. Elbanhawi, M. Si mic, and R. N. Jazar, Frontiers in Artificial Intelligence and Applications, vol. 262, pp. 513-522, 2014.
- [8]. H.Marzbani, M. Si mic, M. Fard, and R. N. Jazar, "Better Road De3sign for Autonomous Vehicles Using Clotho ids,in Intelligent Interactive Multimedia Systems and Services,vol.40,2015,pp. 265-278