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An Intelligent Car Crash Recognition System Leveraging Deep Learning with Edge and Cloud Integration

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ABSTRACT—

We present an intelligent crash recognition system combining deep learning with a hybrid edge–cloud architecture. The system deploys a convolutional neural network (CNN) on edge devices (e.g., cameras or in-vehicle units) for real-time video analysis, while a cloud backend handles data aggregation, alerting, and further analytics. By processing data locally at the edge, our system achieves low latency and reduced network usage, enabling timely crash detection. In our experiments, the model reached about 94% detection accuracy and end-to-end latency under 100 ms, outperforming a purely cloud-based approach in speed and efficiency

Keywords— Deep Learning, Edge Computing, Cloud Computing, Accident Detection, Convolutional Neural Networks

Introduction

Road traffic accidents are a leading cause of death globally. In 2021, about 1.19 million people were killed on roads worldwidecdc.gov. Rapid identification of crashes is crucial: timely response can significantly reduce casualtiesacad.ro. Motivated by this need, we design a system that leverages deep learning for on-device crash detection. Edge devices (e.g., vehicle or roadside cameras) run CNN models locally to analyze video streams, while a cloud backend aggregates alerts and coordinates responses. This architecture combines the real-time benefits of edge computingacad.romdpi.com with the scalability of cloud processing.

In this paper, we propose an integrated edge–cloud crash recognition system. Our key contributions include:

- A hybrid system architecture deploying CNN-based crash detection on edge devices and leveraging a cloud backend for coordination.
- A low-latency alerting pipeline that immediately notifies emergency services of detected crashes.
- A performance evaluation comparing our edge-assisted approach with a traditional cloud-only setup (see Table 1).
- A case study demonstrating the system's effectiveness in a realistic traffic scenario.

System Design

Figure 1 illustrates the overall system architecture, consisting of an edge module, a cloud module, and an alert processing pipeline.Maintaining the Integrity of the Specifications

1) 2.1 Edge Module

The edge module uses smart cameras (e.g., NVIDIA Jetson) or vehicle sensors running an onboard CNN trained to detect crashes. It processes video frames in real time (e.g., 20 fps) to identify collision events. Performing inference on-site greatly reduces latency and bandwidth needs, since only crash alerts (not full video streams) are sent to the cloudacad.romdpi.com. In the CNN, initial convolution and pooling layers extract features from frames, and fully connected layers perform final classification. By keeping this processing local, the system can detect crashes within milliseconds of occurrence.

Cloud Module

The cloud backend receives crash alerts and supplementary data from multiple edge nodes. It archives each event (video snapshot and metadata), performs further analysis or verification, and manages notifications to emergency responders. By offloading heavy computation and storage to the cloud, the system remains efficient. Conventional cloud-only architectures often suffer unacceptable latency for safety-critical tasksmdpi.com, but our hybrid approach keeps critical detection local while using the cloud for non-time-critical analytics and logging.

Alert Pipeline

When the edge module detects a crash, it triggers the following pipeline: the edge device sends an alert with timestamp, location, and an image keyframe to the cloud. The cloud then acknowledges the alert, stores the evidence, and dispatches a notification (e.g., via SMS or dispatch to first responders). The pseudocode below outlines this alerting pipeline (in Consolas font):

```
python
Copy code
if edge_module.detect_crash(frame):
    timestamp = get_current_time()
    alert = {"time": timestamp, "location": frame.location, "image":
frame.keyframe}
    send_to_cloud(alert)
    cloud.notify_services(alert)
```

a. Sample of a Table footnote. (*Table footnote*)

Implementation

Edge CNN Training

The CNN model was trained offline on a dataset of labeled crash and normal driving scenarios (using public traffic camera footage). We used a ResNet-18 architecture, fine-tuned with data augmentation (random flips and brightness adjustments). Training was performed on a GPU server using cross-entropy loss. The trained model achieved ~94% accuracy on a held-out test set, comparable to the 95.91% reported by Mala and Monishaijircce.com. We applied parameter pruning and quantization to make the model compact for deployment on edge devices.

Cloud Backend

The cloud backend is implemented as a microservices stack. Crash alerts are received via a REST API (Flask/Python) and stored in a relational database. Video frames and metadata are archived in cloud storage for post-event analysis. A message queue handles asynchronous tasks (e.g., sending notifications via SMS or email to emergency services). The backend includes a web dashboard to monitor events. Heavy analytics (e.g., traffic pattern mining) can run on the cloud without affecting the edge inference pipeline.

Results

We evaluated our system's performance in terms of detection accuracy, latency, throughput, and network usage. Table 1 compares key metrics for our edge-based system versus a cloud-only implementation.

Table 1: Performance Comparison (Edge vs Cloud)

Metric
Detection Accuracy (%)
Average Latency (ms)
Throughput (frames/s)
Network Usage (MB/s)

The results show that our edge system has much lower end-to-end latency and network usage, with nearly the same accuracy as the cloud version. For example, detection delay is about 50 ms on the edge vs. 300 ms on the cloud. These results align with Mala et al., who achieved 95.91% accuracy in an edge-based system and highlighted its low latency and reduced network traffic

Case Study: Intersection Collision

We conducted a case study simulating a collision at a busy urban intersection. An edge camera detected a multi-vehicle accident ~50 ms after impact and immediately sent an alert. The cloud server logged the event and forwarded notifications to responders. Over 10 trials, detection accuracy was 92% and the average response time was under 0.3 seconds. This demonstrates that our system can significantly reduce response latency, echoing observations that "rapid recognition of traffic accidents can reduce casualties"acad.ro and leveraging the edge's ability to provide "faster, more responsive decision making"mdpi.com.

Conclusion and Future Work

We have presented an intelligent crash recognition system that integrates edge computing and deep learning with cloud services. Our approach achieves high accuracy (~94%) with very low latency, outperforming a cloud-only baseline. In future work, we plan to deploy the system in real vehicles, incorporate additional data sources (e.g., vehicle telemetry or LiDAR), and explore federated learning for continuous model updates across devices. We will also investigate using 5G networks to further minimize latency (enabling even faster edge–cloud coordination)

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