

routes/ — Pages

/ — Dashboard (Home)

File: `routes/+page.svelte`

The main operator screen. A CSS grid layout combining six components into a single view.

Components: `Double_Video`, `Map`, `NavigationPlan`, `TaskCompletion`, `IMU`, `Model` (3D scene).

/navigation — Navigation

File: `routes/navigation/+page.svelte`

The navigation task screen. Focuses on map-based rover guidance.

Layout: a 2×2 grid with the map top-left, navigation plan and IMU bottom-left, double video feed top-right, and costmap bottom-right.

Components: `Map`, `NavigationPlan`, `IMU`, `DoubleVideo` (depth + front cameras), `Costmap`.

/maintenance — Maintenance

File: `routes/maintenance/+page.svelte`

The maintenance task screen. Focuses on the rover arm and diagnostics.

Layout: left side has two video feeds (arm camera and depth camera) each with a side panel for arm feedback and arm position data. Right side shows the maintenance task list.

Components: `Video` (arm camera), `Video` (depth camera), `MaintenanceTasks`.

/probing — Probing

File: `routes/probing/+page.svelte`

The probing task screen. Used when the rover is searching for and picking up probes.

Layout: map top-left, interest locations and probes list top-right, double video bottom-left, pickup mode toggle and IMU bottom-right.

The page reads and syncs `pickup_mode` from the backend on mount, and toggles it via the Drive/Pick-up Mode button, which also switches camera 1 between the depth camera and arm camera.

Components: `Map`, `InterestLocations`, `Probes`, `DoubleVideo`, `IMU`.

/science — Science

File: `routes/science/+page.svelte`

The science task screen. Used when the rover is collecting and analysing rock or soil samples.

Layout: left side has a map and double video feed with small side panels for locations of interest and the pickup mode toggle. Right side is fully occupied by the `SamplingLocations` component.

Like the probing route, it syncs `pickup_mode` on mount and switches camera 1 between depth and arm camera accordingly.

Components: `Map`, `DoubleVideo`, `SamplingLocations`.

/settings — Settings

File: `routes/settings/+page.svelte`

The settings page. Contains developer and diagnostic utilities, not used during rover operation.

Diagnostic controls: Ping Rust, Clear Cache, Ping UDP, Ping GPS, Ping pH — these call the corresponding backend commands and are used to verify the Tauri bridge and UDP connection are working.

Dummy stream controls: Start/Stop dummy IMU stream, Start/Stop full dummy stream — start or stop the backend simulator for development without hardware.

File management: List, view, and delete files from the `tasks/`, `images/`, and `maps/` storage directories. Files can be clicked to view their contents inline.

Snapshot: Saves a single JPEG frame from port 5000 as a test image.

Model debug: Calls `debug_resource_dir` and prints the result to the console — useful for verifying model bundling in a production build.

IP check: Fetches the operator laptop's public IP from `api.ipify.org` and displays it. Useful for network configuration when connecting to the rover.

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