

rover_state.rs — Rover Mode State

The state described here MIGHT be subject to change

Manages the three global boolean flags that track the rover's current operating mode. The state is held in a `RoverState` struct registered as Tauri managed state (initialised in `lib.rs`), so it persists for the lifetime of the application.

State fields

State	Default	Description
<code>drive_manual_mode</code>	<code>true</code>	Whether the rover driving is in manual control
<code>arm_manual_mode</code>	<code>true</code>	Whether the arm is in manual control
<code>pickup_mode</code>	<code>false</code>	Whether the rover is in driving or pickup mode

Commands

`get_state(state_type: StateType) → bool` Returns the current value of the requested state flag. Called on page mount to sync the UI with the actual rover state.

`set_state(state_type: StateType, value: bool)` Sets a state flag. Called by the frontend when the operator switches modes (e.g. toggling pick-up mode on the dashboard).

`StateType` is an enum with variants: `DriveManual`, `ArmManual`, `Pickup`.

Revision #3

Created 2026-04-14 09:32:59 UTC by Candela Cimadevilla Gonzalez

Updated 2026-04-15 14:53:59 UTC by Dmytro Khorsun