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Q1. → Request lifecycle (fastAPI / Express)

- * client sends HTTP request
- * Router matches URL + method
- * Middleware layer executes
- * Dependency Injection resolves DB
- * Controller processes logic.
- * Response serialization (JSON)
- * Response middleware → It sent back to client

FASTAPI is more structured & type-safe, express is flexible
but developer disciplined.

→ Middleware :-

Middleware executes before/after route handlers.

Examples :-

- JWT auth verification
- Request logging.
- Rate limiting
- CORS handling.

@app.middleware("http")

async def log_requests(request, call_next):

response = await call_next(request)
return response.

→ Authentication (JWT / OAuth2)

- JWT → stateless, scalable, ideal for robot APIs
- OAuth2 → for human users or third party access.

flow :-

1. Login → generate JWT
2. Store token (client)
3. Validate JWT in middleware
4. Inject user/robot identity into request context.

→ Async vs Sync.

↓ ↓
it handles I/O it blocks threads ~~for~~ bad for high
(DB, API, MQTT) concurrency.
efficiently.

- * fastAPI async → ideal for robot telemetry & logs ingestion.
- * Node.js async → event-loop based (non-blocking).

→ scalable Backend folder structure:

app /

- api/routes
- core (config, security)
- models
- schemas
- services
- db

- main.py * It separates business logic, transport & data.

PART D - SYSTEM DESIGN.

Q16. Multi-Cameras Inspection System.

- cameras publish inspection results to the backend.
- data is stored in a database and displayed on a dashboard.
- failure results trigger alerts automatically.

Q17. Live AMR Dashboard.

- ROS2 data is sent via MQTT to the backend
- The backend streams it to the UI using web-sockets
- Location history is stored for analysis.

Q18. White Label API.

I wrap the vendor API behind my own API layer.
This lets me control authentication, error handling, logging and data format.

Q19. Easy level:

```
def sort_tasks(tasks):
    return sorted(tasks, key=lambda x: x['priority'])
```

PART C - ROS.

Q12. ROS2 concepts

Nodes handle computation, topics stream data, and services support request-response communication. Use a bridge node to send ROS2 data to backend APIs.
 Robotics → Backend via bridge Node.

Q13. Vision Results to Backend.

→ MQTT works best for real time vision data.
 → webhooks are event based and polling are alternatives but less efficient.
 In this case, MQTT preferred.

Q14. Vision Data schema:-

I store camera ID, timestamp, inspection result, confidence score, and bounding box details.
 In this way I design a schema for vision inspection results.

Q15. Message Queues:-

→ RabbitMQ is good for reliable task execution.
 → MQTT is ideal for robots and IoT systems
 → kafka works well for high-volume analytics data.

PART-B - Devops:

Q9. Docker & CI/CD

A docker image is a blueprint of the app, while a container is a running instance of that image.

In CI/CD, it usually:

- Run tests
- Build the application
- Create a Docker image
- Deploy automatically

Q10. Cloud Deployment (AWS):-

I deploy the app on EC2 using Docker. Nginx acts as reverse proxy, and a load balancer helps distribute traffic across multiple instances. Horizontal scaling via ASG.

Q11. Logging & Monitoring:

- I log all robot events with robot IPs.
- Logs are centralized so errors and performance issues are easy to track.
- Alerts notify the team when something goes wrong.

Q5. Live Robot Dashboard :-

- for live data, I'd use websockets or MQTT from the backend.
- The frontend listens to updates and refreshes the robot position & logs in real time.
- If data stops coming, the robot is marked offline.

Q6. Tailwind CSS

Pros :-

- It is very fast to build UI
- No CSS conflicts
- Consistent design

Cons :-

- Long class names
- Slight learning curve.

Q7. Pagination & Caching :-

- pagination reduces the amount of data fetched.
- caching using tools like Redis or React Query avoids repeated API calls and improves performance.

Q8. CORS :-

- CORS controls which domains can access the backend.
- I allow only trusted origins & avoid using wildcard origins in production.

Error Handling

```
{
  "error": "Robot not found",
  "code": 404
}
```

Bonus Enhancements:-

- JWT auth for robots
- SQLite for prototype → PostgreSQL later.
- Dockerized deployment

Q3. State vs props (React)

- props → read-only, passed from parent; configuration
- state → mutable, internal component data; behaviour

Example & when to use:

- Robot card receives robot as props
- online/offline toggles stored in state.

Q4. Component lifecycle:-

- when a component mounts, it renders on screen.
- API calls are usually made inside useEffect.
- when the component updates, it re-renders.
- on unmount, we clean up things like webSocket connections.

→ Idempotency (POST / PUT)

- use idempotency keys
 - PUT is naturally idempotent
 - store request hash + key to prevent duplicates
- ⇒ crucial for robots retrying on network failure

→ Rate Limiting:

→ Prevents abuse & overload.

→ It is Applied at:

- Auth endpoints
- Telemetry ingestion
- Public APIs

Tools : Redis + token bucket / API gateways

Q2. REST API - Robot Management (Design-level)

Endpoints.

POST /robots

PUT /robots/{id}/status

GET /robots

GET /robots/{id}

POST /robots/{id}/logs

GET /robots/{id}/logs

key design decisions :-

- UUID for robot-id
- Logs stored append-only
- status updates partially PATCHable
- clear HTTP codes (201, 404, 409)