ROVER X1 Quadruped Robot Quick Start

Original Instructions

Issue: V1.1

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SHENZHEN DOBOT CORP LTD | China

Disclaimer

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Before using our product, please thoroughly read and understand the contents of this document and related technical documents that are published online, to ensure that the robot is used on the premise of fully understanding the robot and related knowledge. Please use this document with technical guidance from professionals. Even if follow this document or any other related instructions, damages or losses may happen in the using process DOBOT shall not be considered as a guarantee regarding all security information contained in this document.

The user has the responsibility to make sure following the relevant practical laws and regulations of the country, in order that there is no significant danger in the use of the robot.

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Preface

This document describes the functions, technical specifications, installation guide of the quadruped robot ROVER X1, making it easy for users to fully understand and use ROVER X1.

Scope of application

- ROVER X1 (Point-foot edition)
- ROVER X1 (Wheeled-foot edition)

Intended audience

- This document is intended for:
- Customer
- Sales Engineer
- Installation and Commissioning Engineer
- Technical Support Engineer

Revision history

Date	Version	Revised content
2026/03/23	V1.1	Updated the description related to the remote controller
2026/02/25	V1.0	The first release

Symbol conventions

The symbols that may be found in this document are defined as follows.

Symbol	Description
DANGER	Indicates a hazard with a high level of risk which, if not avoided, could result in death or serious injury.
WARNING	Indicates a hazard with a medium level or low level of risk which, if not avoided, could result in minor or moderate injury, robot damage.
NOTICE	Indicates a potentially hazardous situation which, if not avoided, could result in robot damage, data loss, or unanticipated result.
NOTE	Provides additional information to emphasize or supplement important points in the main text.

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1. Safety Instructions

1.1 Disclaimer

ROVER X1 is an all-around intelligent quadruped companion robot **(strictly prohibited for military use).** However, as robotic technology is not yet fully mature at this stage, you must pay particular attention to the safety instructions provided in this manual during actual operation.

Any safety information provided in this document should not be considered as a warranty from SHENZHEN DOBOT CORP LTD (hereinafter referred to as “DOBOT”). The robot may cause injury or damage even if all safety instructions are observed.

- DOBOT is not responsible for any damage caused during the transportation and handling of the robot.
- Natural wear and tear of components and battery aging are considered normal risks, for which DOBOT does not assume liability.
- Unauthorized disassembly, modification, or unofficial repair of the robot is strictly prohibited. DOBOT shall not bear any responsibility for malfunctions or damages resulting from such actions.
- ROVER X1 is only suitable for individuals aged 14 or older who possess the corresponding cognitive and behavioral capabilities. Individuals who do not meet these requirements must use the product under the guidance and supervision of a guardian and must read the manual carefully before use. DOBOT assumes no responsibility for robot damage or personal injury caused by improper operation or failure to follow the product’s instructions for use.
- The robot's default maximum walking speed ranges from 1.8 m/s to 3 m/s. If a higher walking speed is required, please contact technical support. When operating the robot at high speed, you must exercise extreme caution. DOBOT shall not bear any responsibility for damage to the robot or personal injuries resulting from improper operation.
- It is strictly prohibited to use the robot under environmental conditions that are not recommended. DOBOT shall not bear any responsibility for damages to the robot caused by improper operating environment.
- The obstacle avoidance function is enabled by default when the robot leaves the factory. DOBOT shall not assume any responsibility for risks arising from the user's decision to deactivate this function.
- DOBOT reserves the final right of interpretation and the right to update the terms regarding ROVER X1.

1.2 Operating environment

Recommended environment

- 5°C to 35°C, under clear weather conditions.
- An open area spacious enough for the robot to move freely, and it must not be operated in crowded locations.
- The ground must be hard, flat, and free of foreign objects.

Unsuitable environments

Do not use the robot in the following environments!

- Strong wind, rain, snow, fog, lightning, extreme heat, cold, or other severe weather conditions.
- Humid, dusty, or chemically corrosive environments.
- Areas with electromagnetic interference or Wi-Fi signal disruption.
- Complex, slippery, cluttered, or surfaces with sharp objects.
- Ice or soft ground (such as thick sponge). On smooth surfaces like tiles, the robot's walking speed must be reduced.

1.3 Usage guidelines

Before use

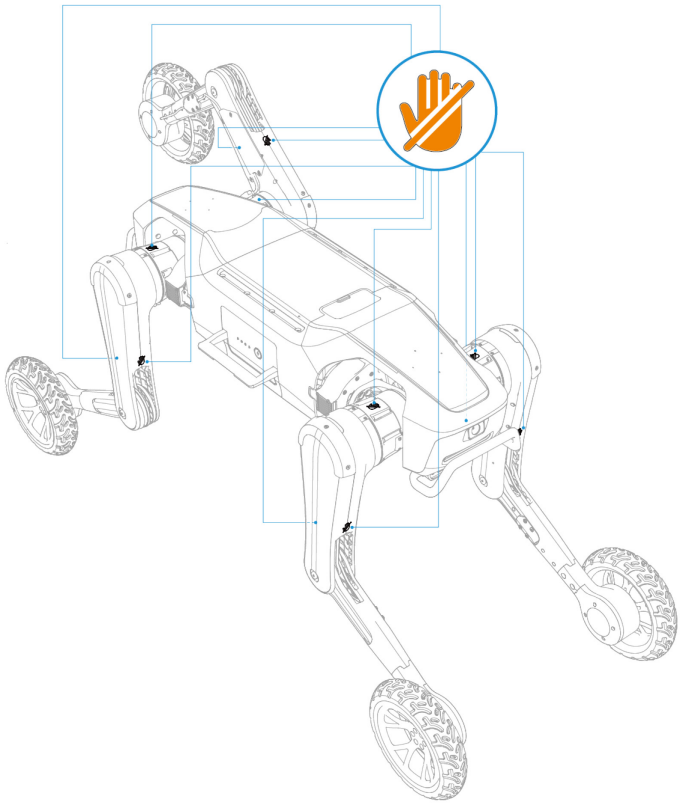
- The operator must ensure they are in good physical and mental condition.
- The operator should be familiar with the robot's various gait modes and emergency stop procedures.
- Only original parts of the robot should be used, and all parts must be in proper appearance and functional condition.
- Check whether the battery pack and the remote control have sufficient charge.
- Check whether the robot's exterior is intact, if all limbs can move flexibly, and if there is any wear on the foot ends. Note that the foot ends are consumables and should be replaced promptly if worn.
- Inspect the robot's interior for any foreign objects (such as water, oil, sand, etc.).
- Check the surfaces of the robot’s camera and depth camera to ensure they are unobstructed.
- Confirm that the robot's firmware has been updated to the latest version.

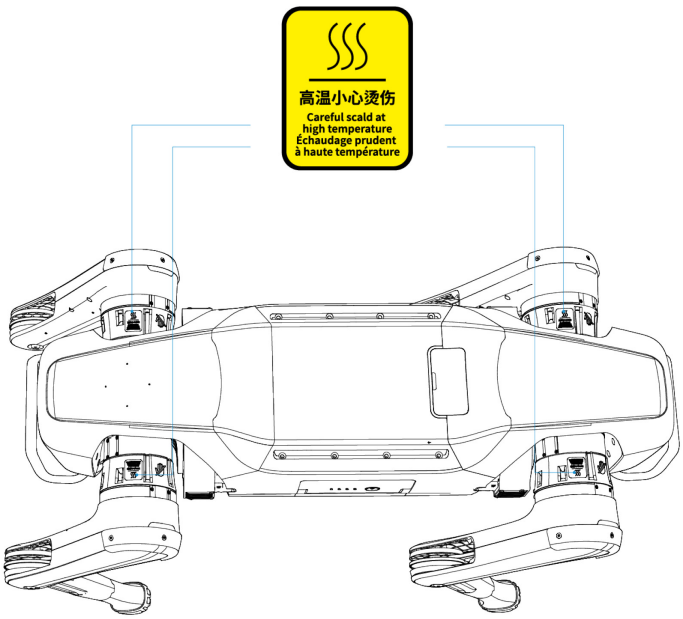
During use

- Ensure the robot remains within sight and maintains a distance of at least 2 meters from obstacles or crowds.
- Do not touch the robot while it is in operation.

NOTICE

The robot's body is labeled with warning stickers indicating pinch and high-temperature hazards. Contact with these areas may result in pinching or burns due to high heat. Please exercise extreme caution.





- Do not continue using the robot if it is damaged.
- Avoid making abrupt adjustments to the robot's posture on surfaces with insufficient friction.
- The robot's rated battery life is 1.5 to 2.5 hours (actual duration varies based on movement speed, load, and terrain).

- The robot can step over obstacles up to 16 cm high and climb slopes not exceeding 30° to 35°. When operating on uneven terrain or steeper slopes, please control the robot carefully to prevent loss of balance and falls.
- If the operating area has a certain slope, it will trigger the obstacle avoidance function of the wheeled-foot robot. It is recommended that users manually disable the obstacle avoidance function and maintain safety precautions when operating on sloped surfaces.
- If the robot accidentally falls into water during operation, disconnect the power immediately.
- In case of a malfunction, contact DOBOT's technical support engineer in time.

After use

- Please power off the robot immediately after use.

2. Product Introduction

2.1 Product overview

ROVER X1 is an all-in-one intelligent quadruped companion robot that integrates features such as motion tracking, entertainment interaction, contextual load handling, and safety protection, specifically designed for modern households and outdoor enthusiasts. By utilizing advanced technologies including intelligent motion control, multi-sensor fusion, and multimodal interaction, ROVER X1 delivers automated services across three core scenarios: fitness logging, travel assistance, and child companionship. This enables the robot to serve as a user's "fitness partner", "camping assistant" and "family helper".

2.2 Core function

Intelligent motion

- **Active Following:** Utilizes vision-based technology to lock onto and follow a designated target person. Maximum following speed: 1.2 m/s (for the point-foot robot) and 2 m/s (for the wheeled robot).
- **Obstacle Avoidance:** Omni-directional perception for both forward and reverse movement, with dynamic planning of safe paths.
- **Intelligent Navigation:** Enables mapping, positioning, navigation, and patrolling in complex environments (subsequent OTA upgrades).
- **Point-Foot/Wheeled-Foot:** A single device supports convenient switching between point-foot and wheeled-foot modes.

Intelligent interaction

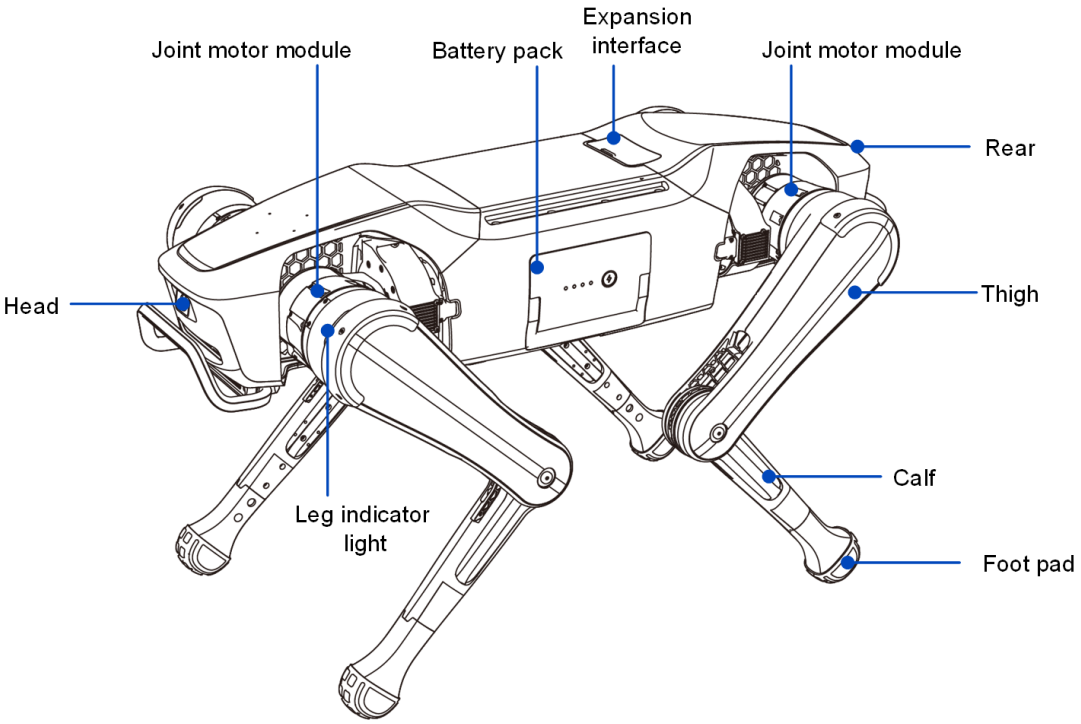
- **Smart Recognition:** Gesture/human/scene recognition
- **Voice:** Supports voice interaction and sound source localization
- **App:** Functional control and real-time video transmission

Intelligent upgrade

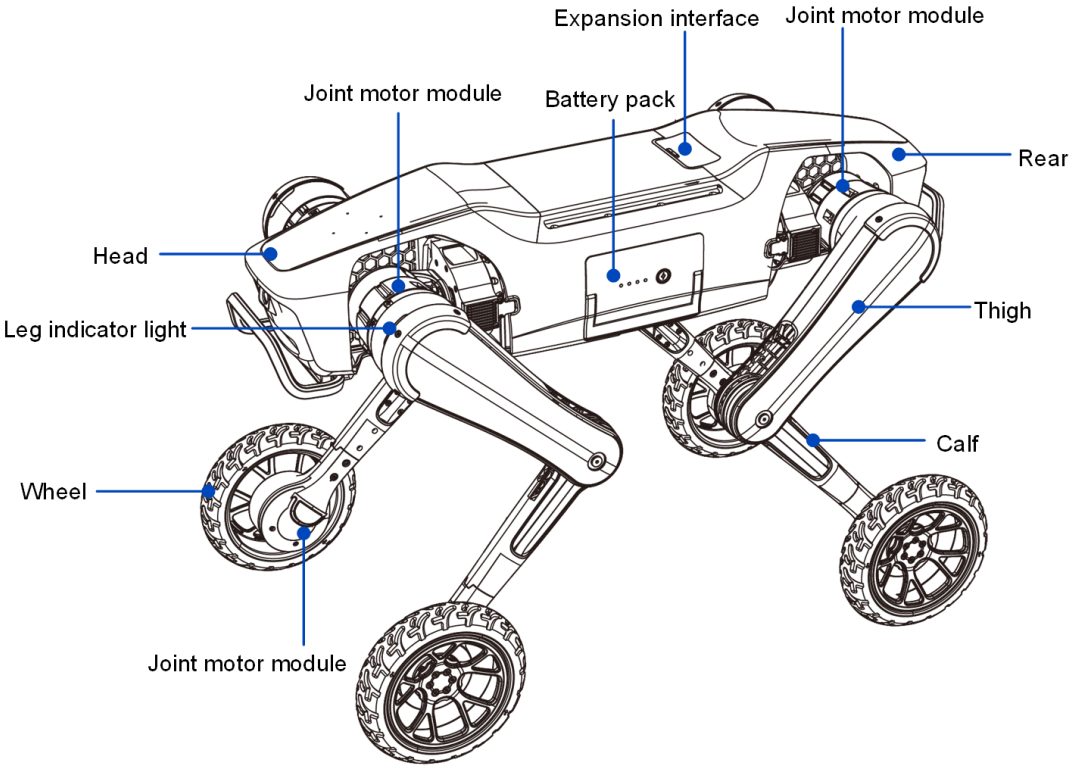
- Supports remote OTA updates.

2.3 Core components of the product

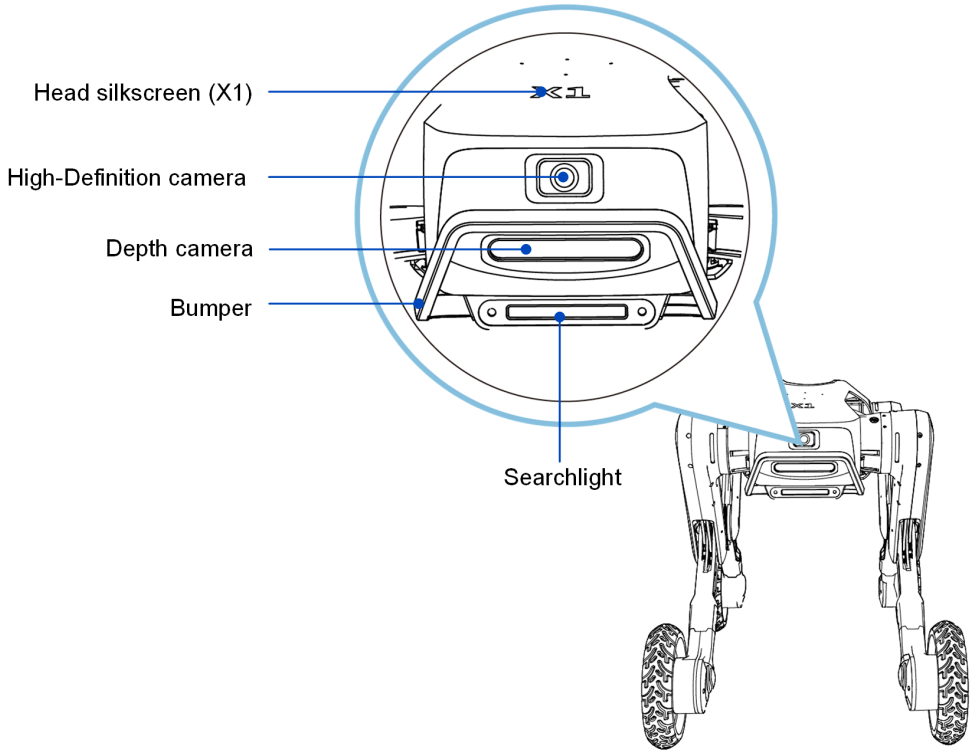
- **ROVER X1 (Point-foot robot)**



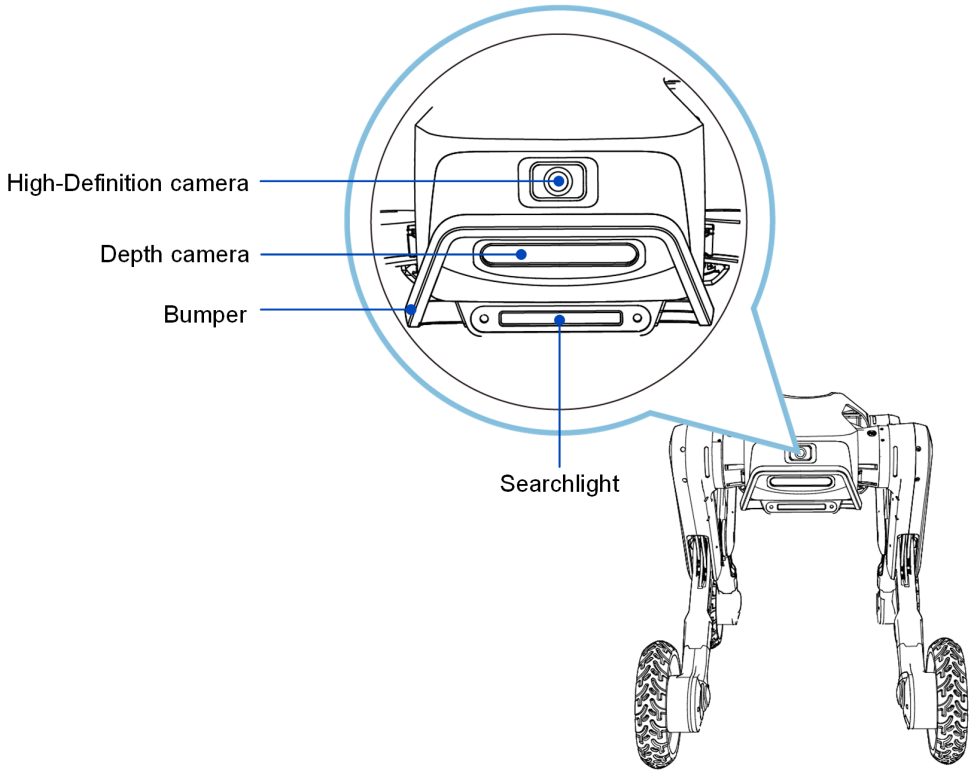
- **ROVER X1 (Wheeled-foot robot)**



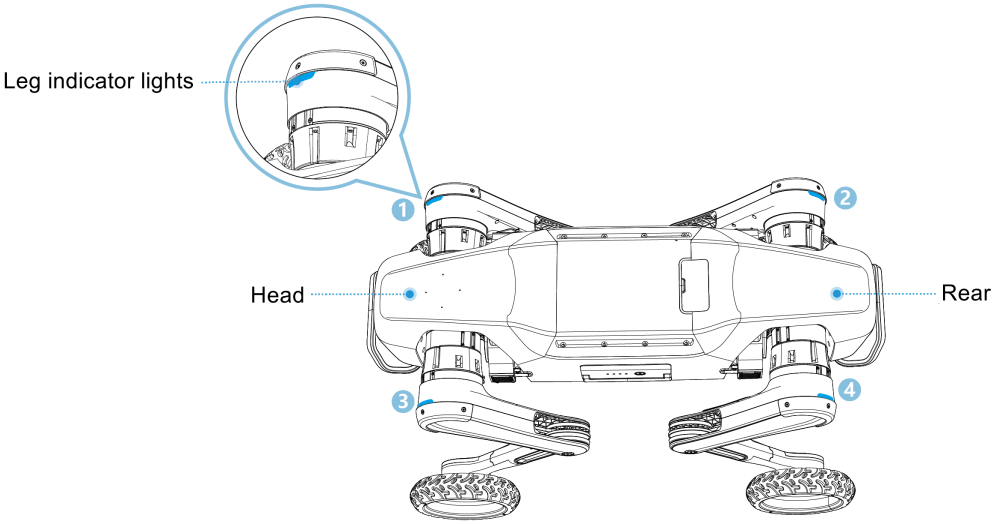
- **Robot Head View**



- **Robot Rear View**



2.4 Leg indicator light status



Priority	Indicator state	Duration	Description
3	Steady green (front legs) Flashing red (rear legs)	Persist unless overridden by another mode	Robot is in motion after successful startup
3	Steady green	Persist unless overridden by another mode	Robot is not in motion after successful startup
2	Flashing cyan	Continuous	Powering on
2	Steady purple	Continuous	Robot in following mode
2	Flashing green	2s	Robot activated by voice command
2	--	--	Obstacle detected; Light signal aborted
1	Flashing red	Continuous	Communication failure
1	Steady yellow	Persist until complete power-off	Power off
1	Flashing yellow	Continuous	Low battery level

NOTICE

- LED states at Priority 3 have the highest precedence.
- Higher-priority LED states override lower-priority ones.

2.5 Technical specifications

Product model		ROVER X1 (Point-Foot)	ROVER X1 (Wheeled-Foot)
Battery capacity / mAh		4000 mAh (Standard edition) 8000 mAh (Extended range edition)	
Battery life / h		1.5 – 2.5h	
Mobility	Maximum speed	1.8 m/s	3 m/s
	Gradeability / °	30° – 35°	
	Step climbing height / cm	16 cm	
	Payload / kg	3 – 7 kg	
AI & Smart features		Path planning and autonomous obstacle avoidance in follow mode AI large model voice Q&A and English dialogue (coming soon)	
Imaging system		Dual 1080p cameras (front and rear) 1920x1080@ 30fps Supports photo capture and video recording	
Remote control		App: Wi-Fi control, 4G remote control	
Bionic motion		Handshake, dancing, jumping	
Follow mode		Visual following	
Obstacle avoidance		Front and rear obstacle avoidance	
Size / mm		761 x 372 x 428 mm	761 x 440 x 516 mm
Weight / kg		15.5 kg	18.5 kg

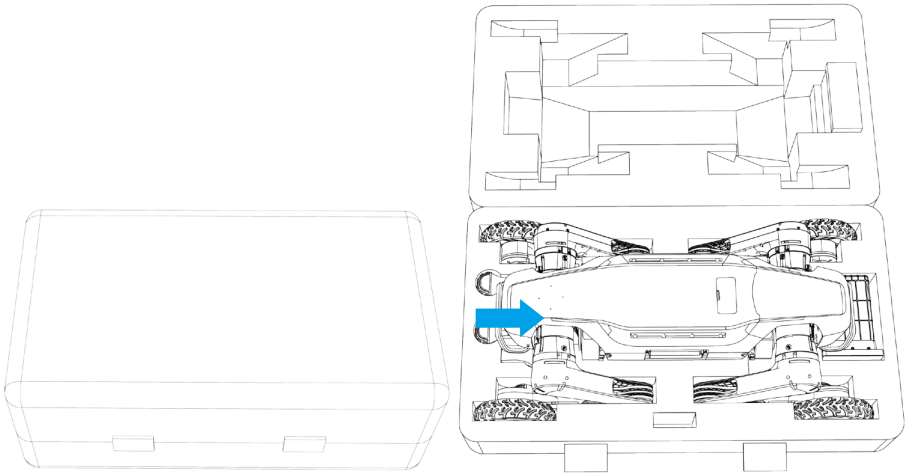
3. Quick Start

3.1 Unpacking

NOTE

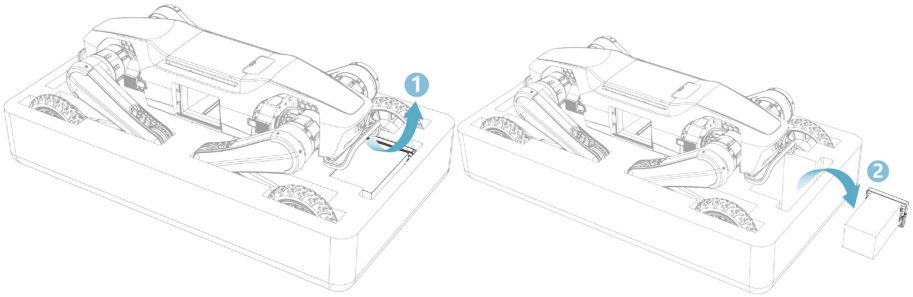
Subsequent related images will use the ROVER X1 (Wheeled-foot) as an example. The ROVER X1 (Point-foot) differs only in product appearance, while the operating procedures remain the same. Please refer to the product you received for accurate appearance details.

1. Upon receiving the robot, please check the outer packaging to ensure it is in good condition. If any damage is found, promptly contact the logistics company and your local supplier.
2. After opening the outer packaging, please verify the items against the unpacking checklist included with the product shipment. If any items are missing, promptly contact after-sales support for a replacement.



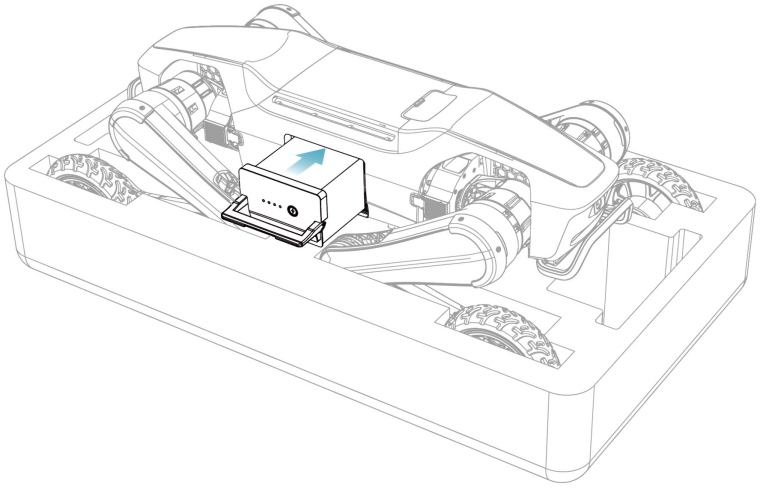
3.2 Power on

1. Gently lift the robot's bumper and remove the battery pack from the packaging box underneath the robot.

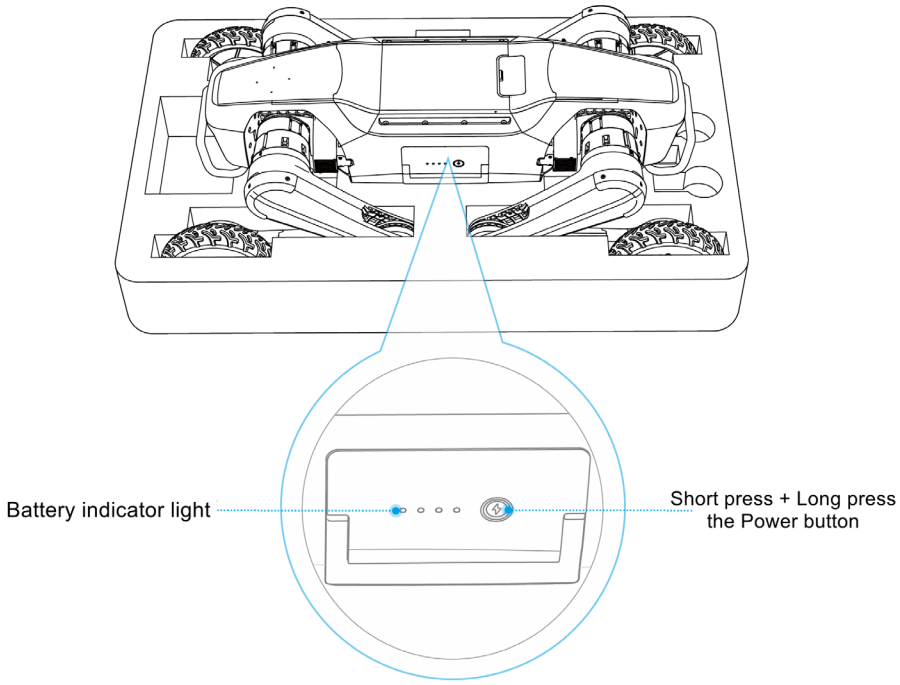


2. Briefly press the power button on the battery pack to check its power level (the number of illuminated indicator bars represents the remaining battery charge). If the battery charge is insufficient, please refer to the instructions in the Battery pack charging section to fully charge the battery pack first.

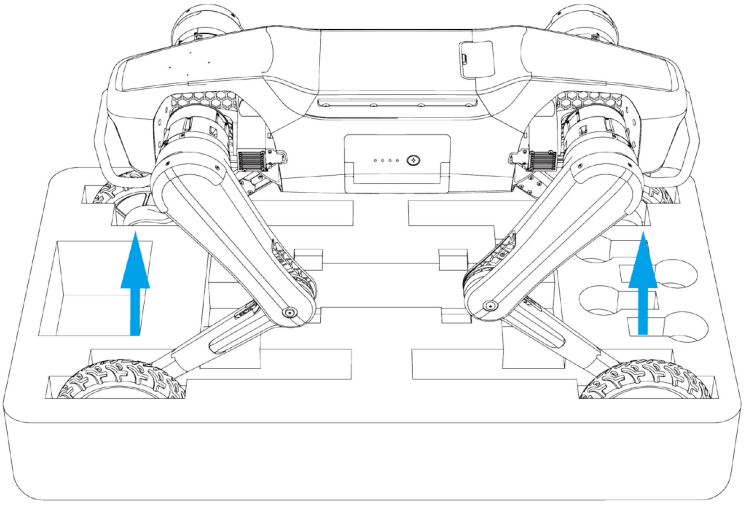
3. Keep the handle vertical and insert it laterally into the bottom of the battery pack panel until it is flush with the side surface of the robot. Then lower the handle and snap it into the battery panel to complete the installation.



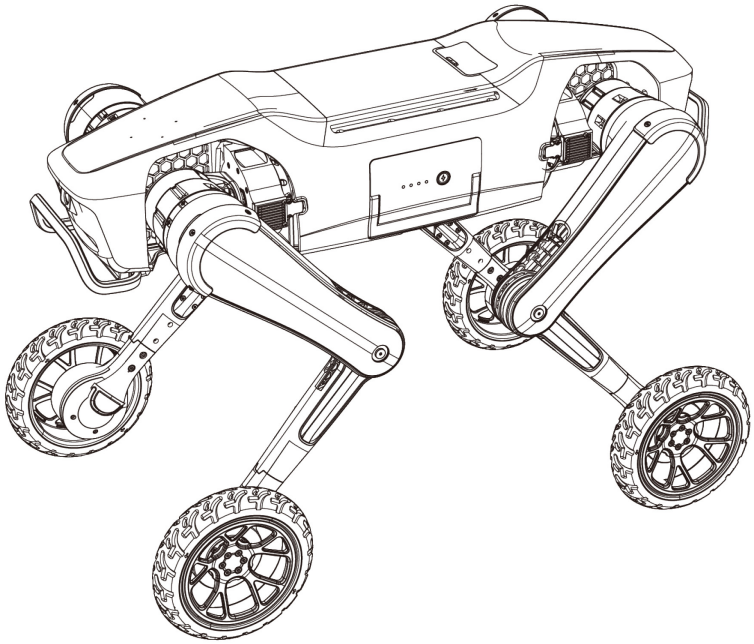
4. To activate the robot, first briefly press the battery pack power button once, then long-press the power button for over 2 seconds.



5. When the robot's leg indicator lights are steadily blue, it indicates that the robot has successfully powered on. After startup, you can control the robot to stand up.



6. Carefully lift the robot out of the packaging box and place it on a hard, flat, and debris-free surface.



NOTICE

- Handle with care to avoid any scratches or damage to the robot's exterior.
- Clear all obstacles around the robot, ensuring it has ample space to move freely. Maintain an area with a diameter of at least two meters centered on the robot, free from obvious obstructions or blockages.

3.3 App binding

NOTICE

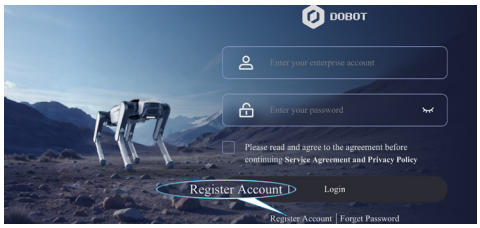
- The App must be bound before using the robot for the first time.
- Due to differences between the Android and iOS platforms, if you switch platforms to log into your account, you will need to re-add the robot.

1. **Download the App:** Android users can scan the QR code to download the app, while iOS users can either scan the QR code or search for "INFFNI ROVER" in the App Store to download it.

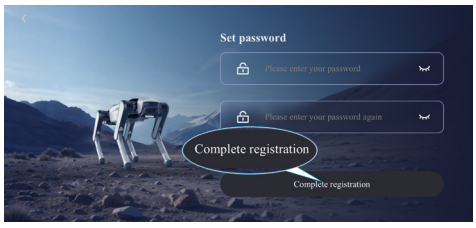
The QR code for Android download

The QR code for IOS download

2. **Register and log in to the App:** You can create a new account via email.



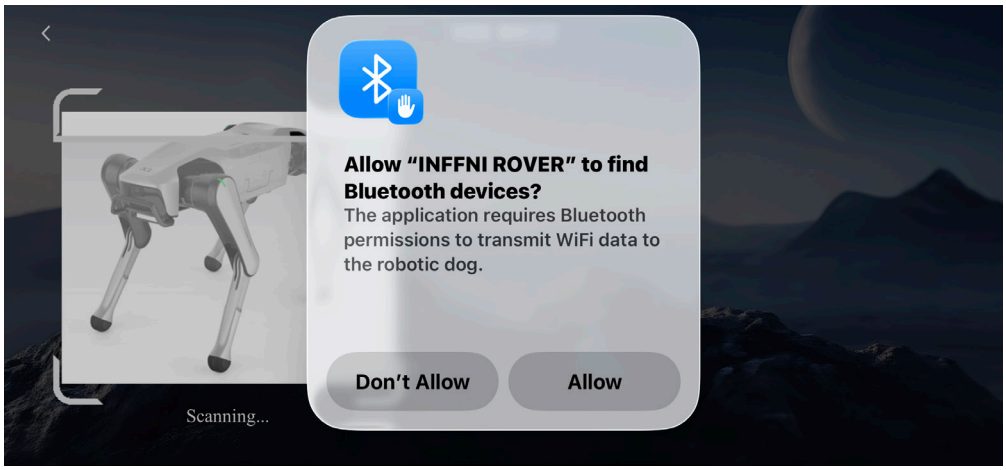
① After opening the App, tap "Register Account".



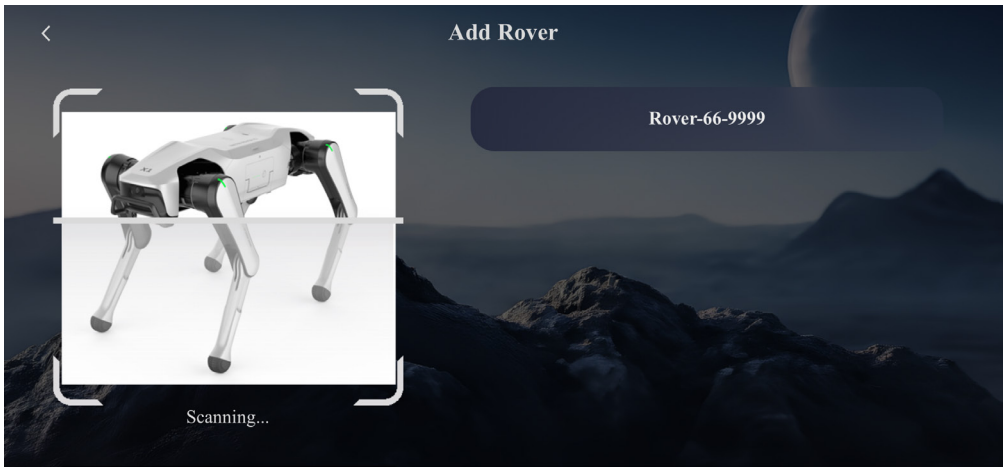
② Enter your email address, obtain the verification code, then input the code and set your account password. Finally, tap "Complete registration".

3. **Add robot:** After powering on the robot, first enable Bluetooth on your mobile device to detect nearby robots via Bluetooth.

① Log in to the App and click "Add ROVER".



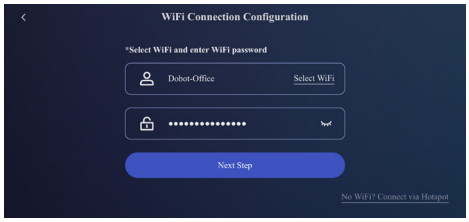
② Tap "Allow" to allow the App to find Bluetooth devices.



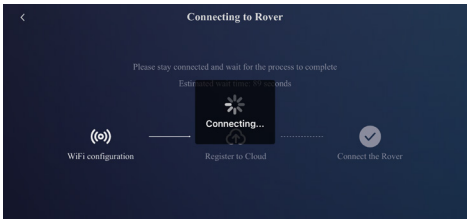
③ Once the scan is complete, nearby robots will be displayed. Tap to enter the "WiFi Connection Configuration" page to bind the robot.

4. **Binding the robot:** The robot can be bound via either Wi-Fi mode or AP mode.

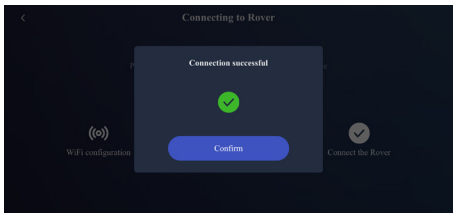
- **Wi-Fi mode:** Ensure both the mobile device and the robot are connected to the same Wi-Fi network, or connect the mobile device to the robot over the internet if the Wi-Fi supports internet access.



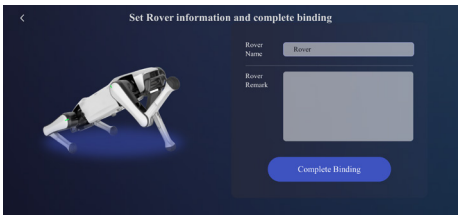
① Enter the Wi-Fi network name and password that both your mobile device and the robot are connected to, then tap "Next Step".



② Robot is connecting. Please wait patiently.



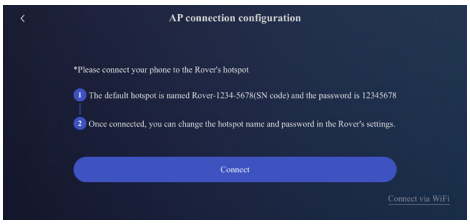
③ Connection successful.



④ Set the robot name and optional notes, then tap "Complete Binding".

- **AP mode:** Connect your mobile device to the robot's hotspot. The hotspot name begins with "Rover-xx (Robot SN)".

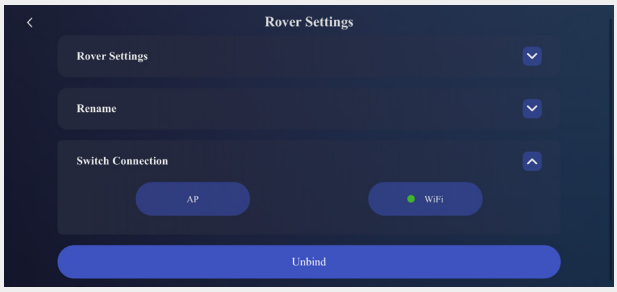
① On the "Wi-Fi Connection Configuration" page, tap "No Wi-Fi? Connect via hotspot" in the lower-right corner.



② Then tap "Connect" to link your phone to the robot's hotspot (name: Rover-xx, password: 12345678). Return to the App. The robot will automatically connect successfully via the AP hotspot.

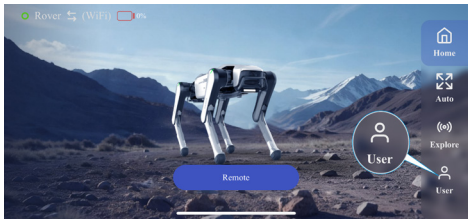
NOTE

If the robot has already been successfully bound via Wi-Fi, you can also switch to AP connection through the App by going to "User > Rover Settings > Switch Connection".

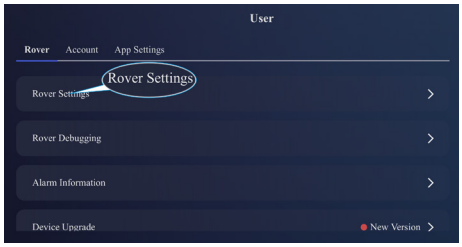


5. **Controlling the robot:** After binding, tap "Remote" to operate the robot.

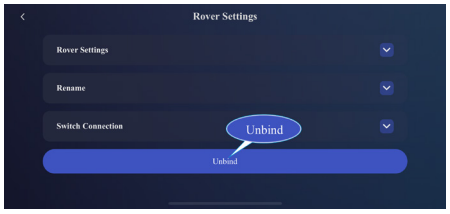
6. **Switching account binding:**



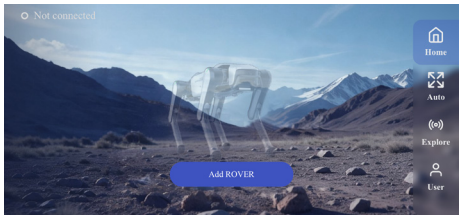
① After the robot is successfully connected, tap "User".



② Then tap "Rover Settings".



③ Tap "Unbind" to remove the current user's binding.

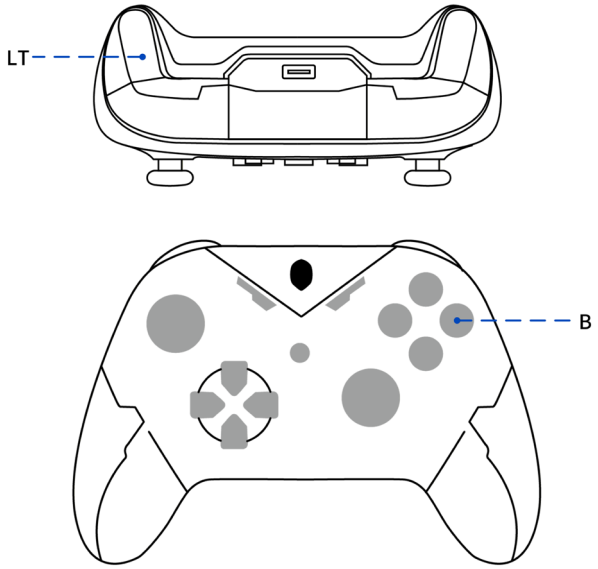


④ Switch to another account and complete the binding process again.

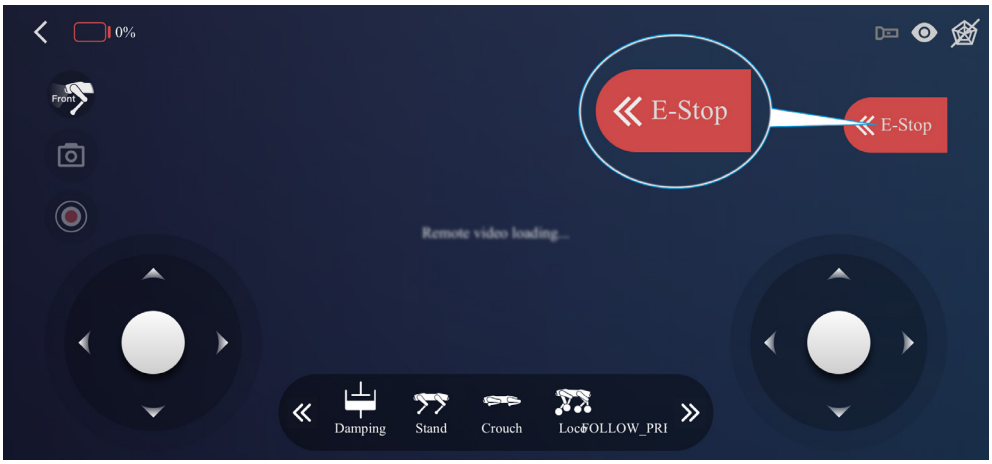
3.4 Abnormal stop

If an unexpected situation occurs while using the robot, users can quickly stop the robot using the following methods. Before operating, please take care to protect the robot to avoid accidental damage.

a) Press the **LT + B** buttons on the remote controller to switch the robot into Ready mode. Once the issue is resolved, the robot can be operated normally again.



b) On the "Remote" page in the App, tap the "E-Stop" button on the right side of the screen to trigger an emergency stop. At this point, the "E-Stop" button will change to "Restore".

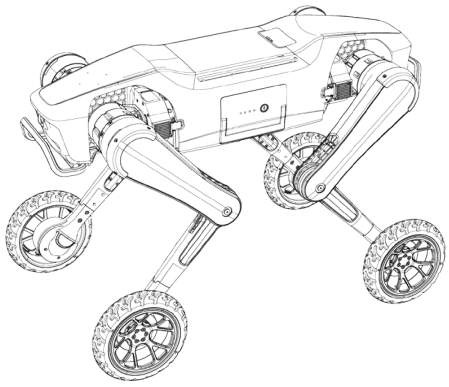


NOTICE

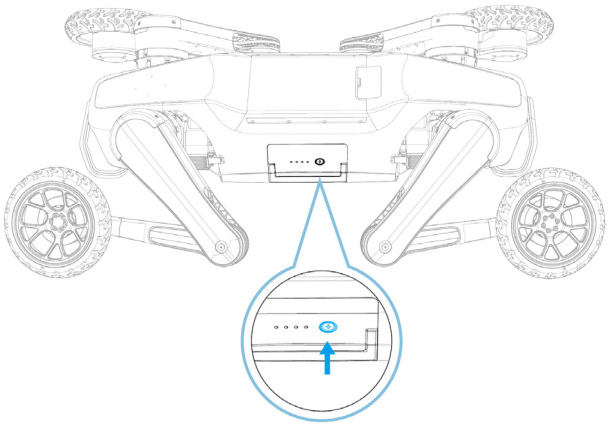
After the emergency condition has been cleared, you must go to the App's "Remote" page and tap "Restore" to release the E-stop before you can operate the robot normally.

3.5 Power off

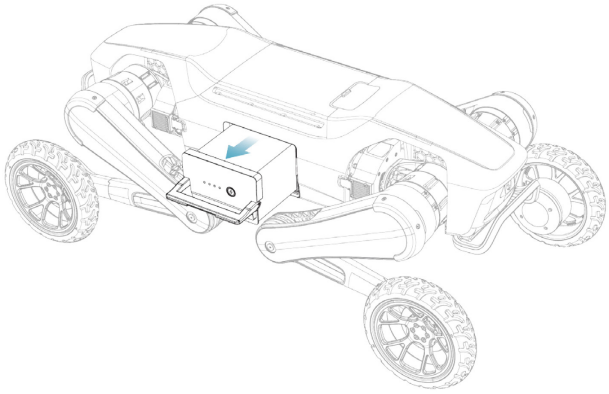
1. Position the robot to stand statically on a flat surface.



2. First, press the robot's power button once briefly, then press and hold the power button for 2 seconds to turn it off.



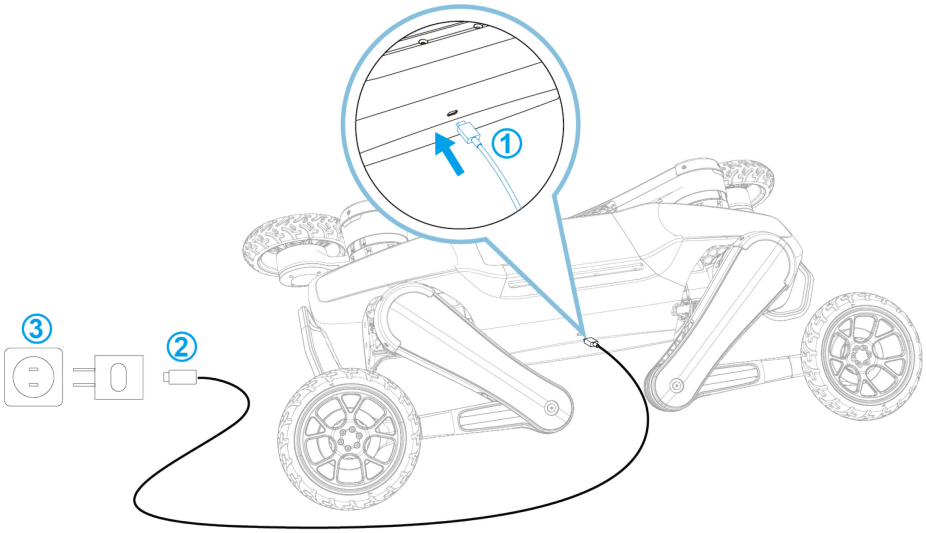
3. After the robot is fully powered off, arrange its upper and lower legs as well as the hip joints for compact storage. If the robot will not be used for an extended period, remove the battery pack and keep it properly.



3.6 Battery pack charging

When the robot's leg indicator light flashes yellow quickly, it indicates low battery power (remaining power is only sufficient for about 20 minutes of use). At this time, you can charge the battery pack using the original charger included in the shipping list.

Before charging, first ensure the robot is statically standing on a flat surface, then control it to lie down (enter a prone state) via the App, voice, or remote controller. Next, briefly press the battery pack's power button once, then press and hold the power button for 2 seconds to turn off the battery pack.



① Connect the Type-C charging port on the side of the robot to the USB charging cable.

② Connect the USB charging cable to the power adapter.

③ Plug the power adapter into an AC outlet and turn on the AC power to begin charging. When all 4 battery indicator lights remain steadily lit, it indicates that the battery is fully charged. Please disconnect the charger in time.

NOTICE

- Please use the original charger provided by DOBOT. Non-official chargers are strictly prohibited for charging the battery pack.
- Before connecting to an AC power source, ensure that the voltage of the AC supply matches the charger's rated input voltage. Failure to do so may damage the charger.
- When all four battery level LEDs are steadily lit, the battery pack is fully charged. Disconnect the charger promptly.
- The battery pack must cool down to room temperature before recharging.
- If smoke, unusual odors, overheating, or deformation occur during charging, immediately unplug the charger.
- If battery electrolyte accidentally gets into the eyes, immediately rinse thoroughly with plenty of clean water and seek medical attention without delay.

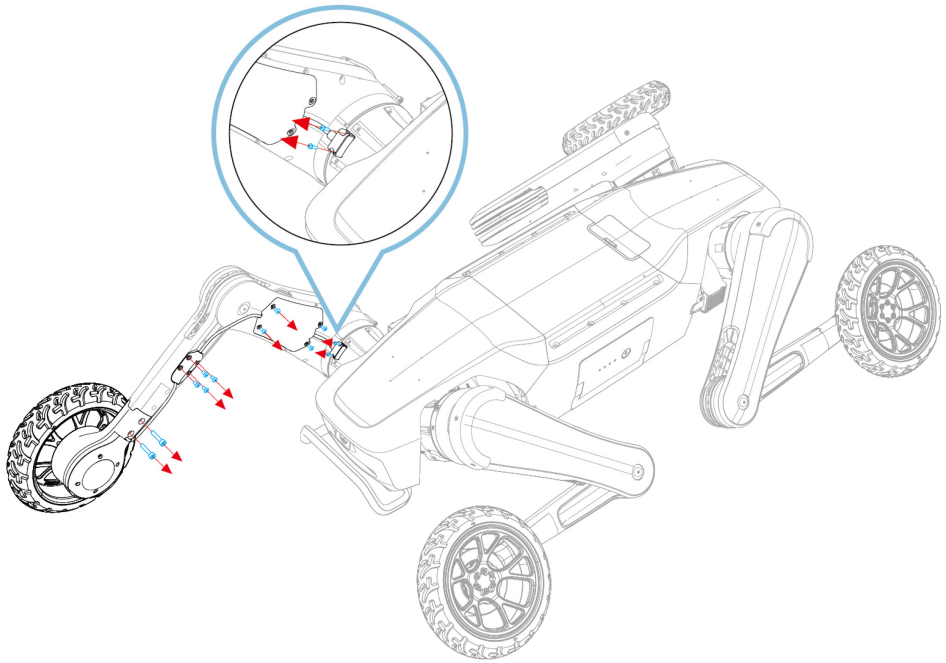
3.7 Point-foot/Wheeled-foot switching

If you have purchased the point-foot + wheeled-foot robot series, the wheels are pre-installed at the factory, and the packaging box includes four point-foot accessories. You can replace the wheeled-foot with point-foot according to the following instructions.

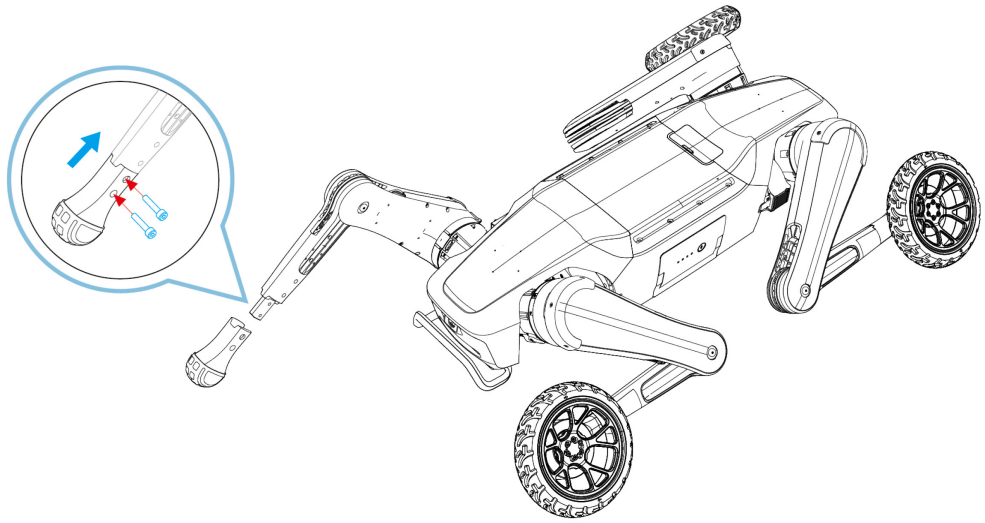
NOTICE

Before replacing the wheeled-foot or point-foot, you must first power off the robot.

1. As shown in the figure below, remove the fixing screws on the thighs and calves of the wheeled-foot, disconnect the wheeled-foot communication cable connector (located near the joint on the thigh), and store the removed wheeled-foot, screws, communication cable, etc., properly in the packaging box.



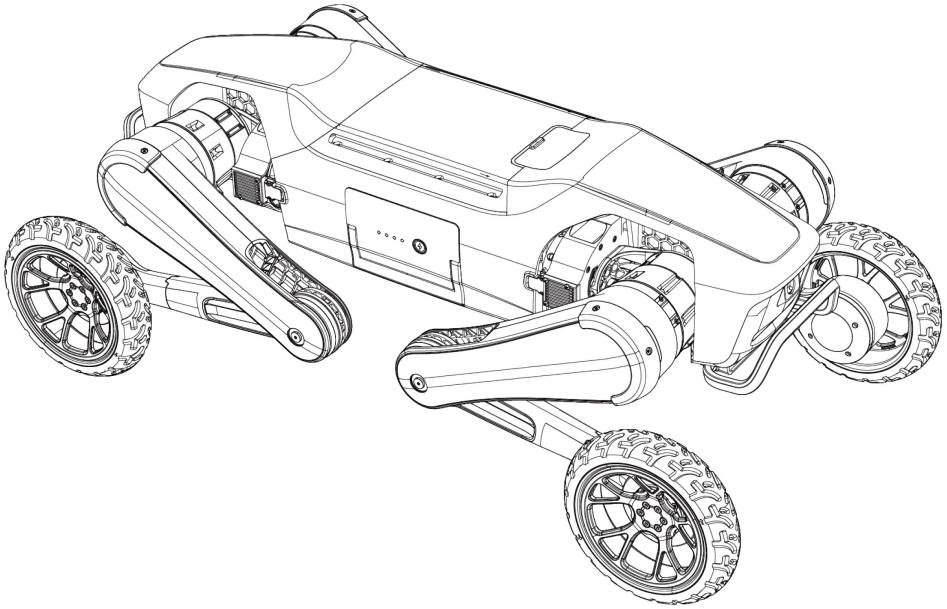
2. Take the point-foot accessory from the packaging box, align and insert the point-foot with the robot's calf, then secure it with screws.



3. Follow the above steps to replace the remaining wheeled-foot units with point-foot units one by one.

3.8 Packing

1. Refer to the instructions for Controlling the Robot and use the App, voice, or remote controller to command the robot to lie down.



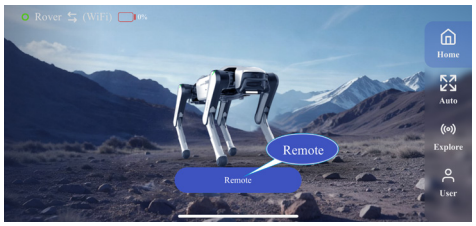
2. Lift the robot and place it into the designated position inside the packaging box.
3. Inside the packaging box, briefly press the robot's power button once, then press and hold the power button for 2 seconds to turn off the robot.
4. Remove the battery pack, gently lift the robot's bumper, and place the battery pack beneath the robot.
5. Place other accessories (remote controller, point-foot accessories, etc.) into their designated positions in the packaging box, then close the packaging box.

4. Controlling the Robot

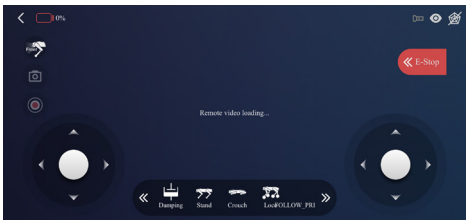
4.1 App control

4.1.1 Access the App control interface

After the robot is successfully paired with the App, click "Remote" on the App homepage to directly control the ROVER X1 robot.



Start remote control

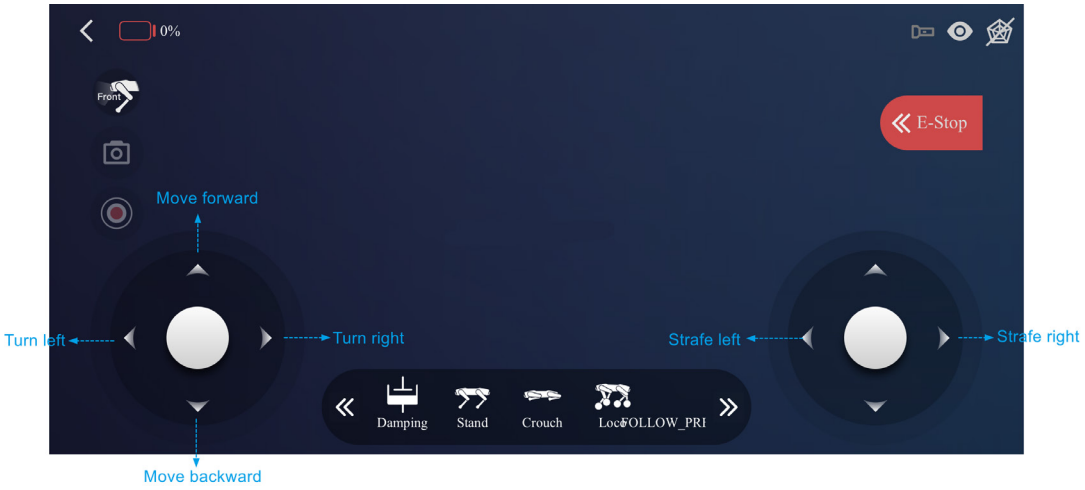


Enable real-time video transmission

4.1.2 App control for robot movement and steering

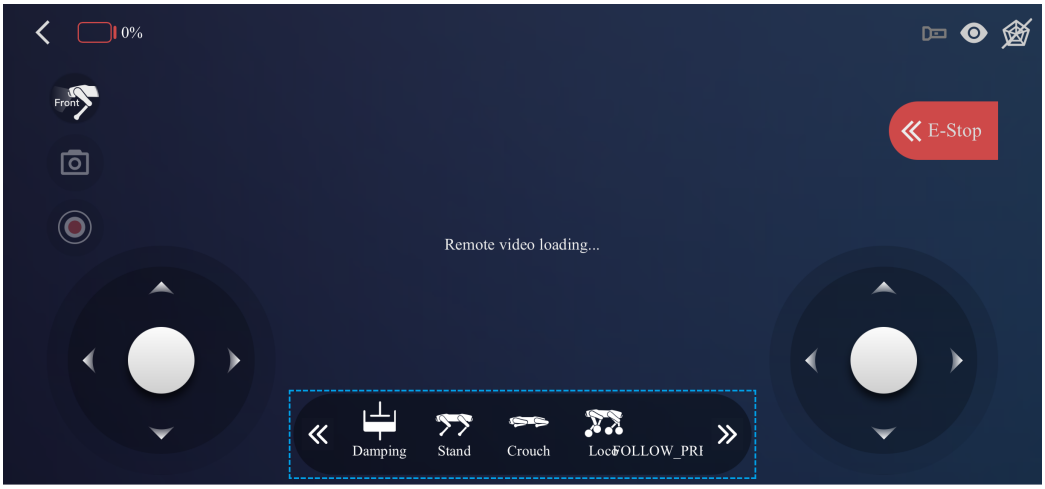
After the robot is bound to the App, on the "Remote" page of the App homepage:

- Tap the △Up / ▽Down arrow on the left directional pad to control the robot to move forward / backward.
- Tap the ◁Left / ▷Right arrow on the left directional pad to control the robot to rotate left / right.
- Tap the ◁left / ▷right arrow on the right directional pad to control the robot to strafe left / right.



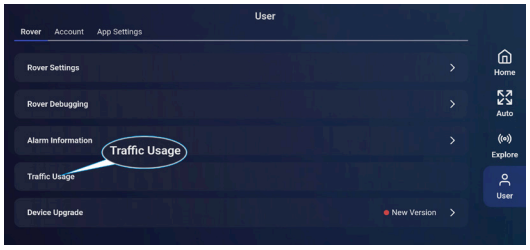
4.1.3 App-controlled robot skill demonstrations

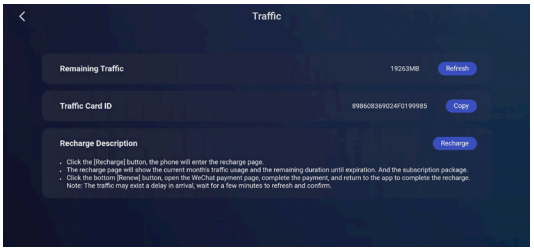
After the robot is bound to the App, on the "Remote" page of the App homepage: Tap the icons below to switch the robot into different postures or perform skill demonstrations. For details about each icon on the App, please refer to Posture illustrations and descriptions.



4.1.4 4G data module

The ROVER robot comes with a built-in 4G IoT card, which can connect to the operator's base station to enable functions such as external network access and remote operation. Each ROVER robot is gifted with 20GB of data upon purchase, valid for 6 months after activation. You can check the remaining data, view the SIM card ID, or top up your data on the "User> Rover > Traffic Usage" page within the App.





NOTE

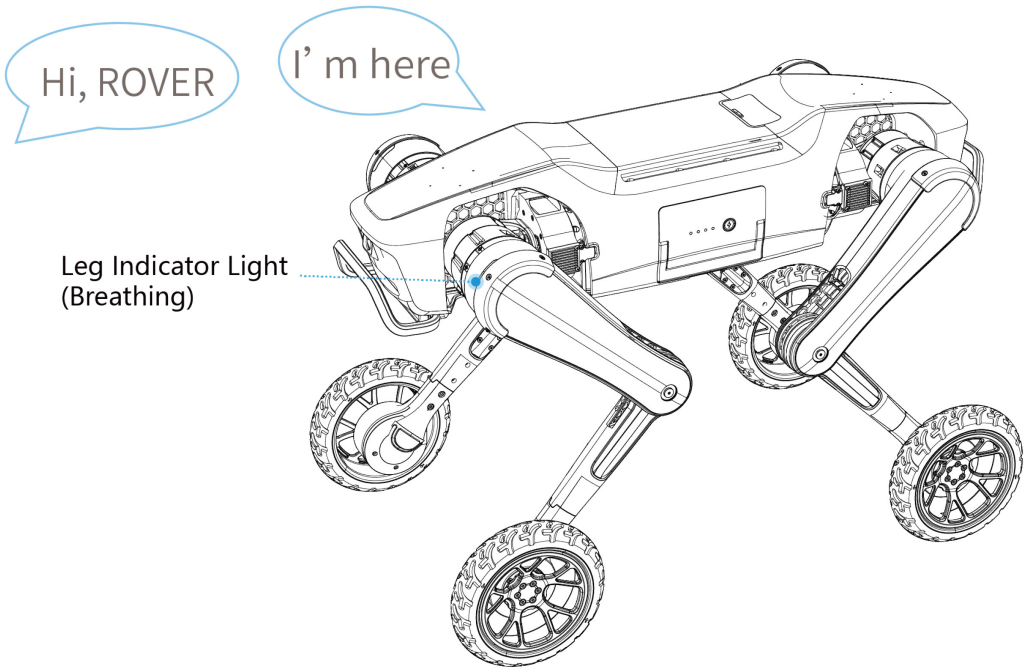
- Running out of data won't affect the robot's normal operation.
- The 4G module can be used without restrictions in China, but is only available in certain overseas regions. Please confirm its availability with a DOBOT sales engineer before use.

The 4G network is automatically enabled based on the principle of "WiFi takes priority to reduce data consumption" without requiring manual activation by the user. Once enabled, the 4G data connection remains active until the robot is powered off. After restarting, the robot will re-evaluate based on the following logic:

When using a WiFi connection, if the WiFi is abnormal or no configured WiFi is detected, the 4G data connection will automatically activate.

4.2 Voice control

Speak the wake word “Hi, Rover” clearly to the robot. The robot will respond with phrases such as “I'm here”, “what can I do for you”, “Good to see you”, “Hey, what do you need”, “Alright, I'm up”, “What's the plan” or “I'm ready”, and its leg indicator light will enter a breathing state. At this point, you can issue voice commands. The robot will respond verbally and execute the commands. The robot’s supported voice commands are listed in the table below.



Voice command	Robot response	Robot action
Hi, Rover	I'm here What can I do for you Good to see you Hey, what do you need Alright, I'm up What's the plan I'm ready	Wake up the robot
Sit down	I will remain on standby	The robot sits down in place
Lie down	I’m here if you need me	The robot lies down in place and simultaneously exits the voice conversation state. If you need to continue sending voice commands, you must wake up the robot again.
Stand up	Standing by	The robot stands up in place

Voice command	Robot response	Robot action
Move forward	Let’s go	The robot moves forward slowly
Move back	I'm moving backward	The robot moves backward slowly
Move left	Attention on the left	The robot moves to the left
Move right	Be carefully	The robot moves to the right
Turn left	Turning left	The robot turns left
Turn right	Turning right	The robot turns right
Dance	Watch my show	The robot starts dancing
handshake	Rover is honor to be at your service	The robot's front legs perform a waving motion
Jump	It's funny	The robot instantly leaps up (with all four feet off the ground)
Stop	Task terminated	Emergency stop
Turn	OK	The robot turns in place
…		…

NOTICE

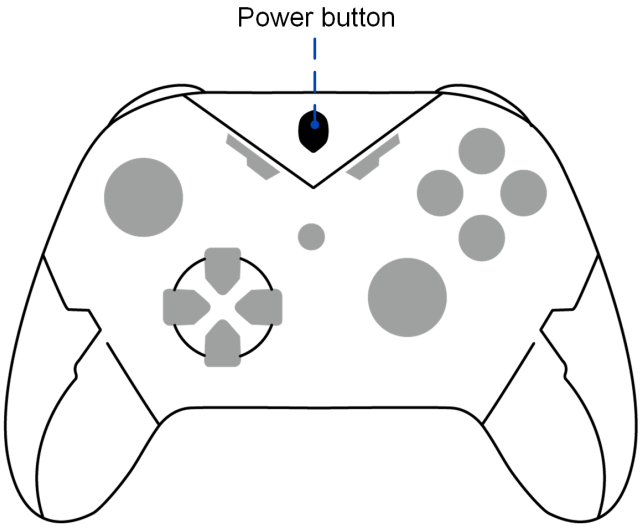
- It is recommended to interact with the robot in a quiet environment, as noisy surroundings may interfere with the accuracy of its speech recognition.
- If the robot fails to recognize commands, you can move closer and try again. For example, attempt voice dialogue at distances of 0.5 meters, 1 meter, and 3 meters respectively.
- After the robot is awakened, the voice dialogue remains active for 30 seconds.
- Speak with clear articulation, at a moderate pace, and with a volume above 60 dB.

4.3 Remote controller

4.3.1 Remote controller button descriptions

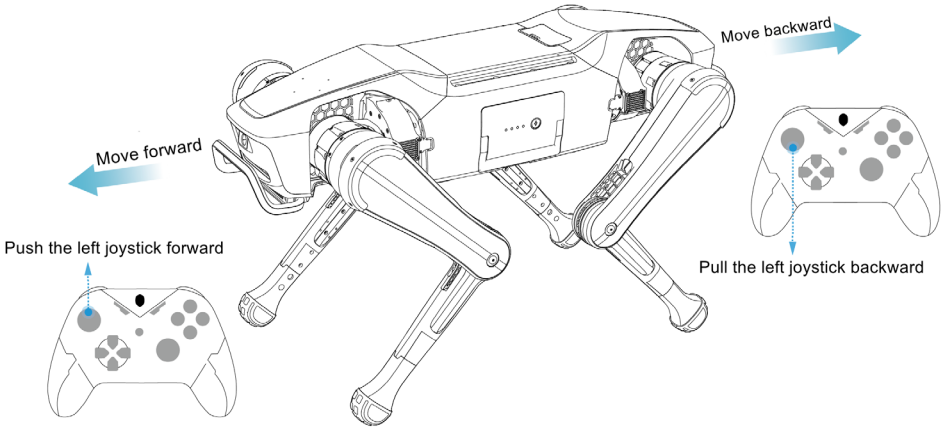
4.3.2 Connect to remote controller

After taking the remote controller out of the packaging box, press the power button in the middle of the remote controller once. The remote controller will vibrate briefly, indicating that it has successfully connected to the robot.

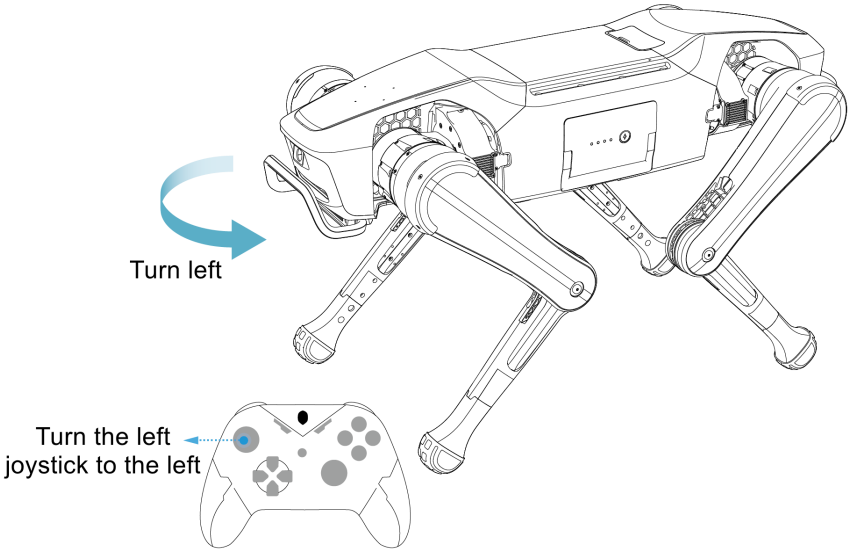


4.3.3 Remote controller control for robot movement and steering

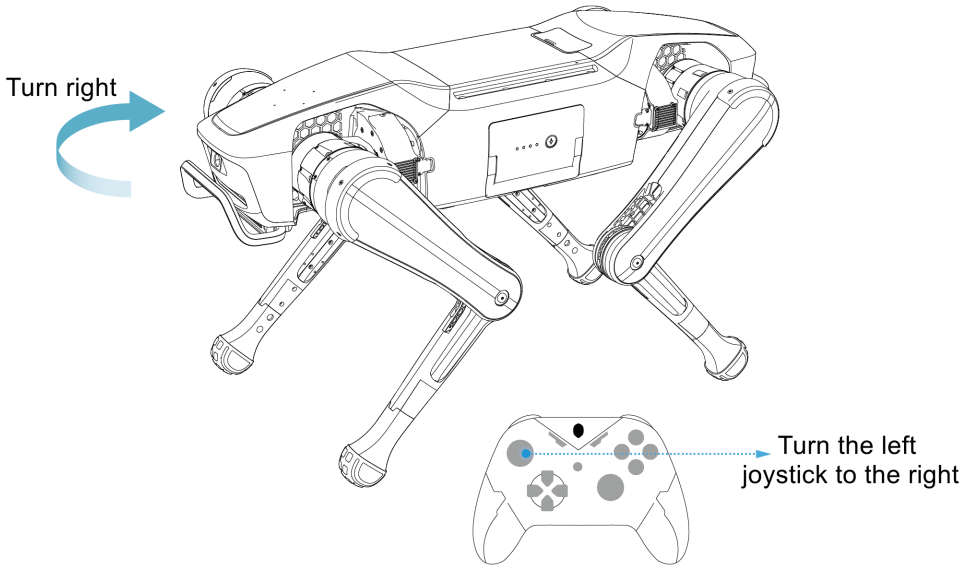
- Push the **left joystick** of the remote controller forward / backward to control the robot to move forward / backward.



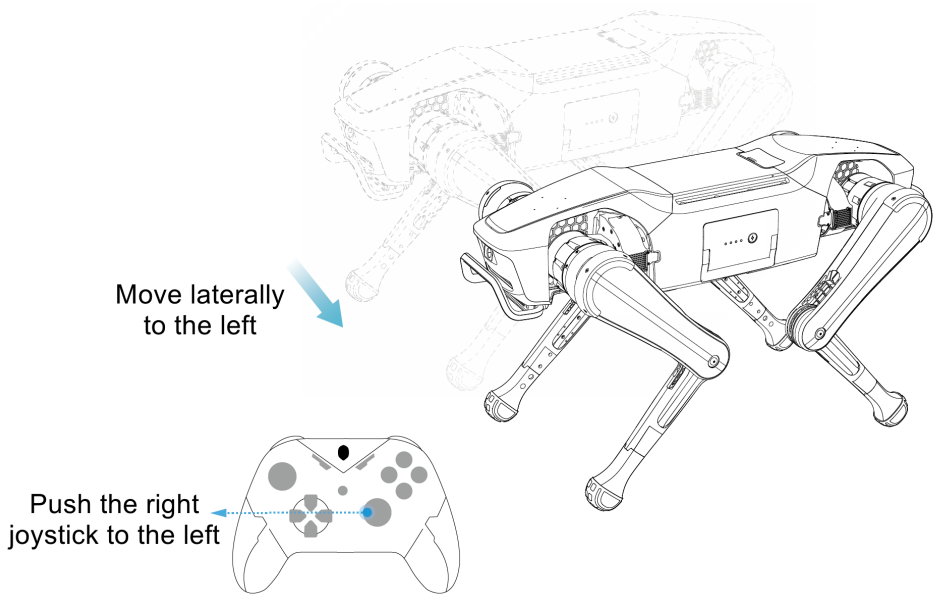
- Rotate the **left joystick** of the remote controller left to control the robot to turn left.



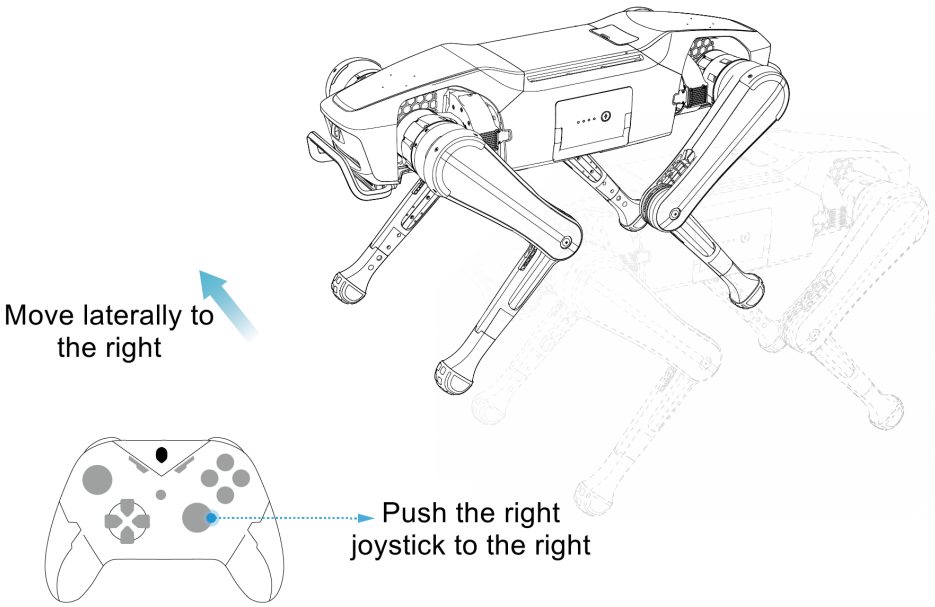
- Rotate the **left joystick** of the remote controller to the right to control the robot to turn right.



- Push the remote controller's **right joystick** to the left to control the robot move laterally to the left.

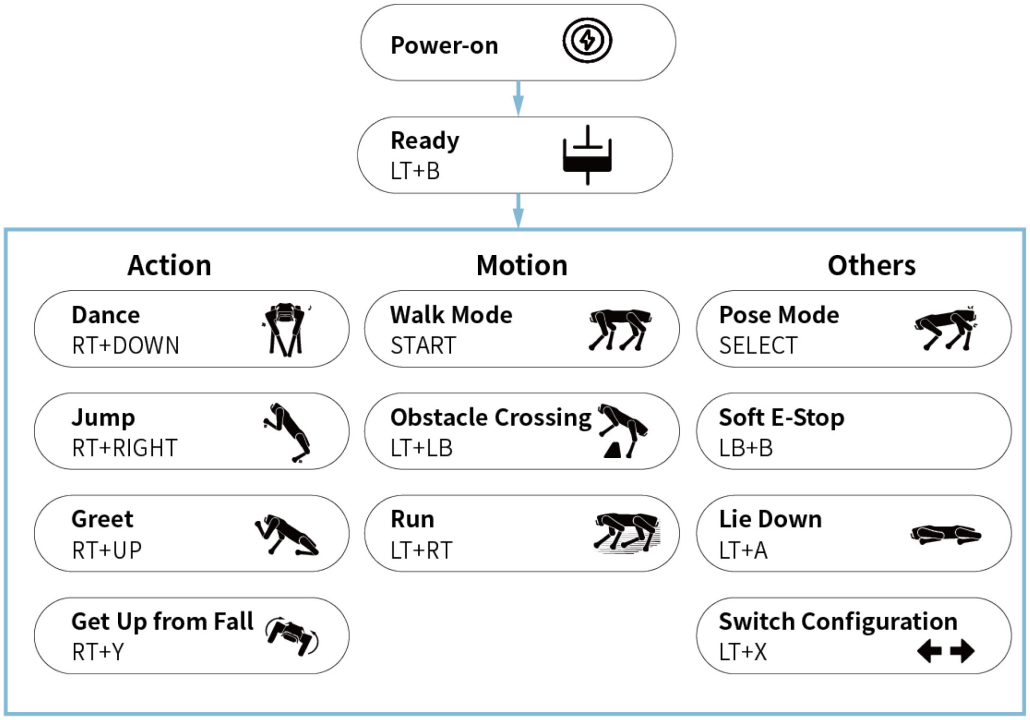


- Push the remote controller's **right joystick** to the right to control the robot move laterally to the right.



4.3.4 Remote-controlled robot skill demonstrations

- **ROVER X1 (point-foot robot)**



NOTICE

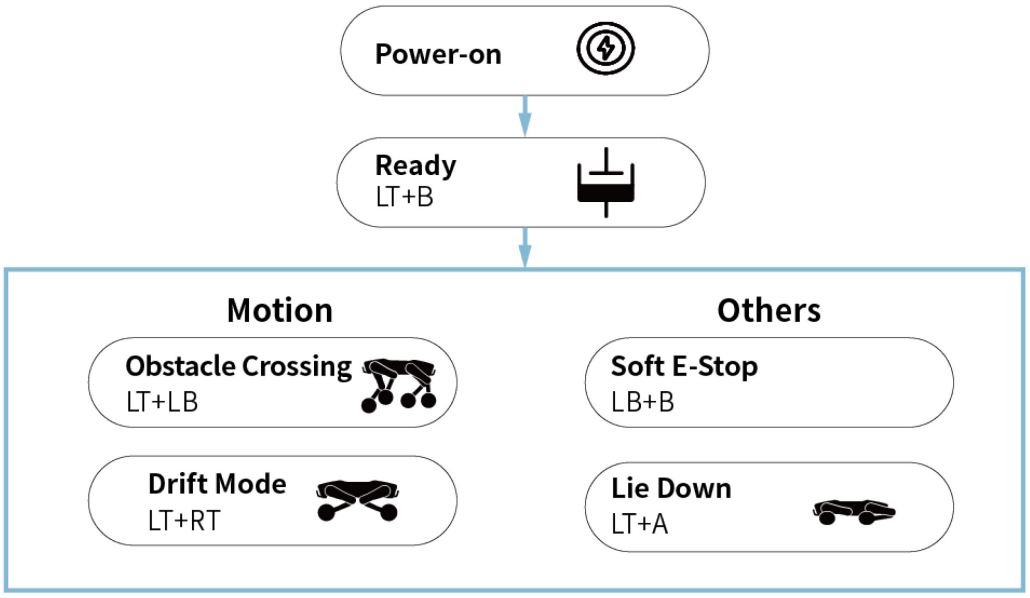
- All the button commands mentioned above will trigger the robot to automatically perform the posture transition.
  - Example: After power-on, the robot is in Ready mode. Simply press **LT + RT (Run)**, and it will automatically transition from **"Standing → Running"**.
- After an **"Action"** command (such as Dance, Jump, Greet) is executed, the robot will automatically return to the **"Walk"** mode.
- **Switch Configuration:** If the triggered action is not supported by the current configuration, the robot will automatically switch to a supported configuration before executing the action.
  - Example: When the robot is in **"Folded Configuration"** and you press **LT + RT (Run)**, it detects that it cannot run in this configuration, it will automatically switch to **"Synchronous Configuration"** first, then start running.
- Due to current limitations in the underlying algorithms, the robot cannot switch configurations directly from a standing posture. When a configuration-switch command is issued, the robot will first **Lie Down → Stand Up → Switch Joint Configuration**. This sequence is normal, not a malfunction.

NOTICE

Soft E-Stop: LB + B

For emergency use only. The robot will smoothly and gently stop all current actions in place.

- **ROVER X1 (wheeled-foot robot)**



NOTICE

Soft E-Stop: LB + B

For emergency use only. The robot will smoothly and gently stop all current actions in place.

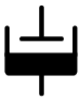
4.4 Posture illustrations and descriptions

4.4.1 Point-foot robot

Posture diagram	Posture name	Description
	Ready	After the robot is powered on, it automatically enters Ready mode. In this mode, the motors of the point-foot robot do not fully release force. The robot switches to Ready mode when abnormal conditions occur.
	Lie Down	A low, stable posture. Used as a preparatory stance before moving or storing the robot, and to self-check whether all joints are functioning properly.
	Synchronous Configuration	Used to self-check whether all joints of the robot are functioning properly. There are two standing postures: **Synchronous Configuration** (legs aligned in the same direction) is the default. Press LT + X to switch to **Folded Configuration** (legs reversed and tucked inward). The robot can be lifted while in either of the two standing postures. In the standing posture, the point-foot robot can activate visual following mode through hand gestures. First, make the  gesture for more than 2 seconds, then immediately switch to the  gesture for over 1 second to enter following mode (the two gestures must be performed consecutively). Make the  gesture to exit following mode.
	Folded Configuration	
	Pose	The robot's posture and height can be adjusted using the remote controller’s joysticks. It is not recommended to lift the robot in this mode (if the robot leaves the ground, leg balance compensation actions may occur).
	Walk	This gait can be used on regular flat ground. Control the robot's movement and steering via the remote controller’s joysticks or the App directional keys.
	Obstacle Crossing	This gait can be used on complex terrain and allows the robot to climb over raised platforms. Control the robot's movement and steering via the remote controller’s joysticks or the App directional keys. ⚠ The robot cannot switch from **Folded**

Posture diagram	Posture name	Description
		Configuration (legs reversed and tucked inward) to the Obstacle Crossing posture.
	Run	The robot walks at high speed. Control the robot's movement and steering via the remote controller's joysticks or the App directional keys. ⚠ The robot cannot switch from **Folded Configuration** (legs reversed and tucked inward) to the running posture.
	Dance	A performance action that does not stop automatically. Switch to Pose mode or Ready mode to end the current action.
	Jump	Instant leap action (All four feet leave the ground). After the leap is completed, it automatically switches to Pose mode. ⚠ The robot cannot switch from **Folded Configuration** (legs reversed and tucked inward) to the Jumping action.
	Greet	A front leg waving action that does not stop automatically. Press **RT + UP** to trigger a "Greet" action again and stop the current action, or switch to Pose mode or Ready mode to also end the current action.
	Get Up from Fall	When the robot falls over (e.g., lies on its side or falls down), press **RT+Y** to make it stand up and reset automatically. ⚠ Pressing **RT + Y** while the robot is standing normally will have no effect. This button command only works when the robot detects that it has fallen.

4.4.2 Wheeled-foot robot

Posture diagram	Posture name	Description
	Ready	After the robot is powered on, it automatically enters Ready mode. In this mode, the motors of the wheeled-foot robot do not fully release force. The robot switches to Ready mode when abnormal conditions occur.
	Lie Down	A low, stable posture. Used as a preparatory stance before moving or storing the robot, and to self-check whether all joints are functioning properly.
	Synchronous Configuration	Used to self-check whether all joints of the robot are functioning properly. There are two standing postures: **Synchronous Configuration** (legs aligned in the same direction) is the default. Press LT + X to switch to **Folded Configuration** (legs reversed and tucked inward). The robot can be lifted while in either of the two standing postures. ⚠ Only when the wheeled-foot robot is in **Folded Configuration** posture can the remote controller's joysticks or App directional keys be used to control the robot's forward/backward movement and left/right turning.
	Folded Configuration	
	Wheeled-foot Obstacle Crossing	Visual tracking mode. First, make the  gesture for more than 2 seconds, then immediately switch to the  gesture for over 1 second to enter following mode (the two gestures must be performed consecutively). Make the  gesture to exit following mode. Control the robot's movement and steering via the remote controller's joysticks or the App directional keys. ⚠ The robot cannot transition from **Folded Configuration** (legs reversed and tucked inward) to the Wheeled-foot Obstacle Crossing posture.
	Drift Mode	Control the robot to move forward, backward, and turn left/right just like driving a car, using the remote control joystick or the App direction keys.

5. Common Issues and Solutions

Issue	Solution
Power-on failure (Red light slowly flashing)	Check the robot's placement and restart, or contact technical support.
App connection failure	Check the network (AP hotspot, connection status corresponding to Wi-Fi mode).
Abnormal standing posture	Contact technical support (Do not calibrate the robot yourself).
The battery level displayed in the App does not match the robot's actual battery level	First fully charge the robot until it is completely powered, then use it until the battery level drops to 10%. After that, fully charge it again to complete the calibration.

NOTE

If you encounter any other abnormal issues during the use of the robot, please contact technical support promptly.

6. Maintenance

Maintenance and repairing must be performed in compliance with all safety instructions in this document.

The purpose of maintenance and repairing is to ensure that the system is kept operational, or to return the system to an operational state in the event of a fault. Repairing includes troubleshooting in addition to the actual repair itself.

Repairing must be performed by an authorized system integrator or DOBOT staff.

Robots or parts returned to DOBOT should follow the instructions below:

- Remove all parts that do not belong to DOBOT.
- Before returning to DOBOT, please make a backup copy of the files. DOBOT will not be responsible for the loss of programs, data or files stored in robot.
- The robot should be restored to its unpacked posture before returning to DOBOT.

6.1 Safety instructions

The following safety procedures and warnings must be observed when operating the robot:

NOTICE

- Replace faulty components with new components of the same model or equivalent components approved by DOBOT.
- Reactivate all deactivated safety measures immediately after completing maintenance work.
- Record all repairs and save them in the technical document associated with the robot system.
- Take necessary precautions to prevent others from re-powering on the robot during maintenance.
- Prevent water or dust from entering the interior of the robot.

6.2 Robot maintenance

To ensure the robot maintains high performance over the long term, regular maintenance checks must be conducted. The personnel in charge of the maintenance must develop a maintenance plan and carry out the necessary tasks. The inspection items are listed in the table below.

Period			Inspection item	Inspection details
Daily	3 months	6 months		
√			Robot storage	• Store in a dry and cool indoor area, avoiding exposure to sunlight and rain; • For long-term storage, remove the battery pack.
√			Robot appearance	• Check if the body is clean, undamaged, or deformed; • Focus on checking whether the camera and radar are dirty or obstructed.
√			Robot cleaning	• Wipe the robot with a dry and clean soft cloth; • Focus on checking whether the camera and radar are wiped clean.
√			Joint	• Check that there is no abnormal noise or vibration from the joints when the robot is running. • After running, touch the joint housing to check for excessive heat.
√			Foot-end parts	• Check for obvious wear on the foot pads. If damage is found, replace them promptly.
√			Battery pack	• Check if the battery pack is securely installed without any looseness; • Check if no visible damage or swelling on the battery pack casing; • Check if the power indicator light displaying normally; • Check if the battery pack is sufficiently charged (when not in use for a long time, it is recommended to maintain a 50% charge and recharge every three months).
√			Remote controller	• Check if the buttons and joystick of the remote controller are functioning properly.

