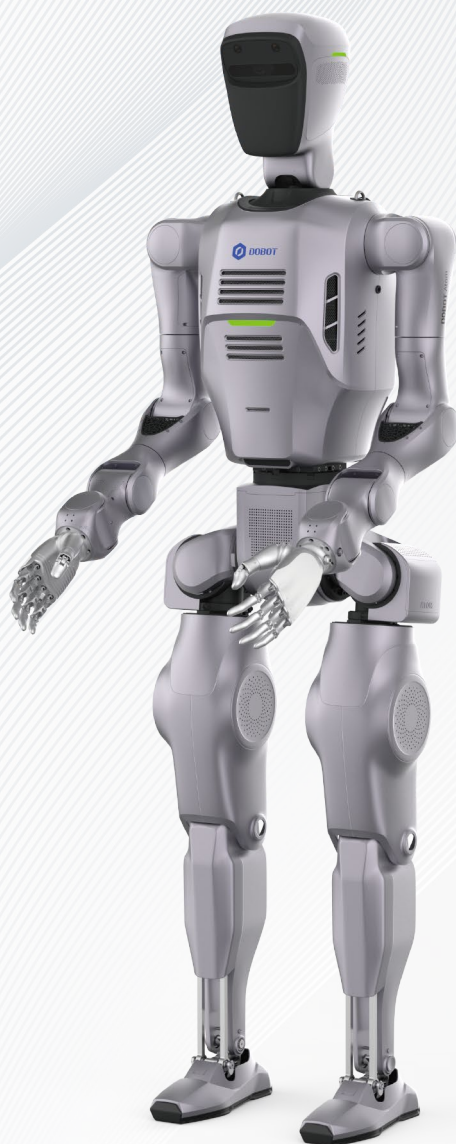




DobotEX App User Guide



Original Instructions

Issue: V1.2.0.0

Date: 2026-08-03

SHENZHEN DOBOT CORP LTD | China

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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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Website: www.dobot-robots.com

Preface

Purpose

This document describes the features and operations of the DobotEX App for the ATOM series humanoid robots, making it easier for you to understand and use the App.

Scope of application

- ATOM - Max
- ATOM - Standard
- ATOM - D
- ATOM-W

Intended audience

This document is intended for:

- Customer
- Sales Engineer
- Installation and Commissioning Engineer
- Technical Support Engineer

Revision history

Date	Version	Revision history
2026/08/03	V1.2.0.0	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.

Contents

Preface	ii
Purpose	ii
Scope of application	ii
Intended audience	ii
Revision history	ii
Symbol conventions	ii
1. Quick Start	1
1.1 Overview	1
1.2 Power on	1
1.3 Connect to App	3
1.4 App main interface	5
1.5 App remote control	6
1.6 Voice control	8
1.7 Robot emergency stop	10
2. Device Settings	12
2.1 Dexterous hands and accessory settings	12
2.1.1 GPIO settings	12
2.1.2 Dexterous hand settings	12
2.2 Joint settings	13
2.2.1 Robot mode	13
2.2.2 Joint information	14
2.2.3 Joint limits	14
2.2.4 Joint brakes (ATOM-W only)	15
2.2.5 Joint calibration	16
2.2.6 Joint motor fine-tuning	16
2.2.7 Overall auto test	17
2.3 View robot data	17
2.3.1 Robot information	17
2.3.2 Software information	17
2.4 View/Clear alarm	18
2.5 Export logs	18
2.6 Switch the interface language	19
2.7 High-speed mode (ATOM-W only)	19
3. Robot Function	20
3.1 Action library	20
3.1.1 Official actions	20
3.1.2 Custom actions	20
3.2 Teleoperation	21
3.3 Radar navigation (ATOM-Max, ATOM-Standard, ATOM-D)	22
3.3.1 New map	22
3.3.2 Creat a new road network	24
3.3.3 Patrol navigation	24
3.3.4 Single-point navigation	25
3.4 Voice assistant	25
3.5 Upper limb / Lift axis control (ATOM-W and ATOM-D only)	30
3.5.1 End position control	31
3.5.2 Wheeled lift axis control	32

1. Quick Start

1.1 Overview

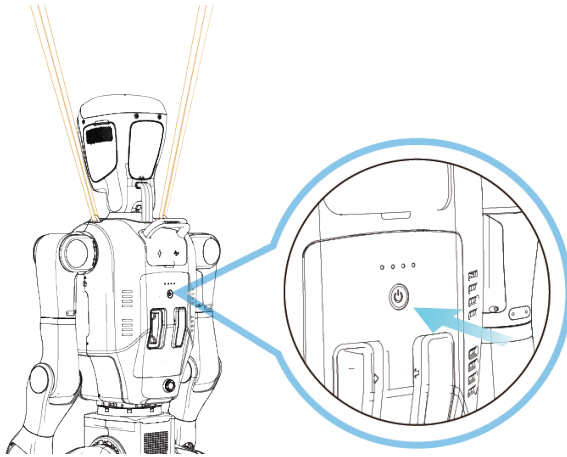
Welcome to the DobotEX App. The DobotEX App is software developed by DOBOT for the ATOM series humanoid robots. With simple interface, easy-to-use functions and strong practicality, it can help you quickly master the operation of DOBOT robots.

The DobotEX App is supported on Android devices, with the compatible version being DobotEX App V1.2.0.0 or later.

1.2 Power on

Before powering on, check that all components are installed and in good condition.

1. Before powering on, please first straighten the robot's head to ensure it is level and facing directly forward.
2. Then short-press the battery pack's power button once, and long-press for 3 seconds. Four indicator lights turning on in sequence and then flashing indicates that the battery pack has been successfully powered on.



NOTICE

- If the robot's head is not properly positioned (e.g., the head is drooping), powering on may trigger a limit alarm.
- The figure shows the ATOM-Max as an example; the operation is the same for other models. Please refer to the actual product appearance.

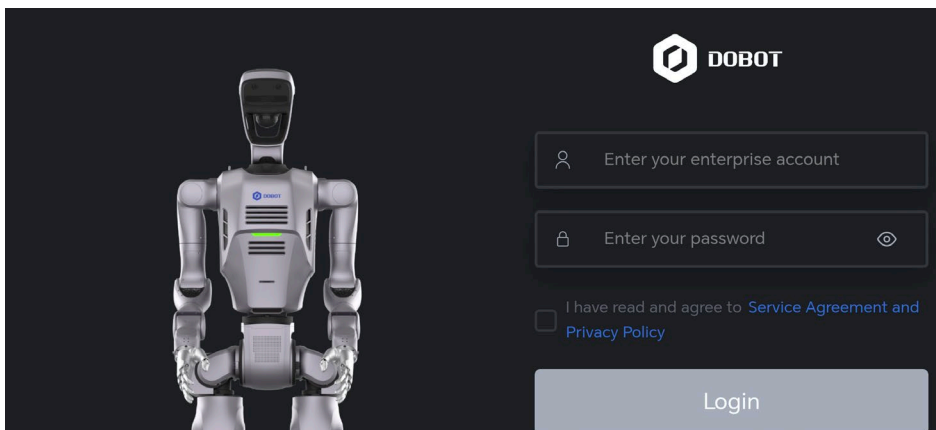
1.3 Connect to App



NOTICE

For first-time use, the robot must be connected to the App.

1. **Download the App:** Please contact DOBOT technical support to obtain the **DOBOT Ex** App installation package and install it.
2. **Log in to the App:** Use the enterprise account and password provided by sales team to log in.

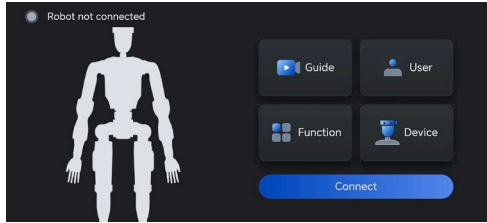


NOTE

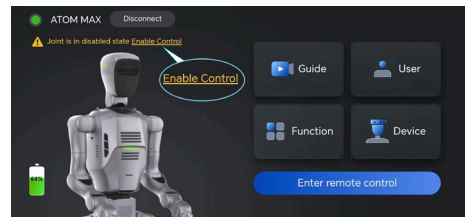
If you do not have a corporate account, please contact DOBOT sales service personnel to obtain one.

3. Connecting to the robot:

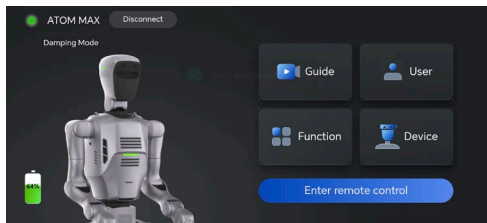
- ① Turn on your phone's WiFi and connect it to the robot's WiFi network (named "ATOM + SN code" or "ATOM-W + SN code", default password: 12345678).
- ② In the App's startup screen, tap **Connect**. When the interface displays the robot appearance, it indicates that the connection has been completed.
- ③ On first startup or after a restart, tap **Enable**. When the robot status is displayed on the interface, the robot has entered the enabled state.



Robot not connected



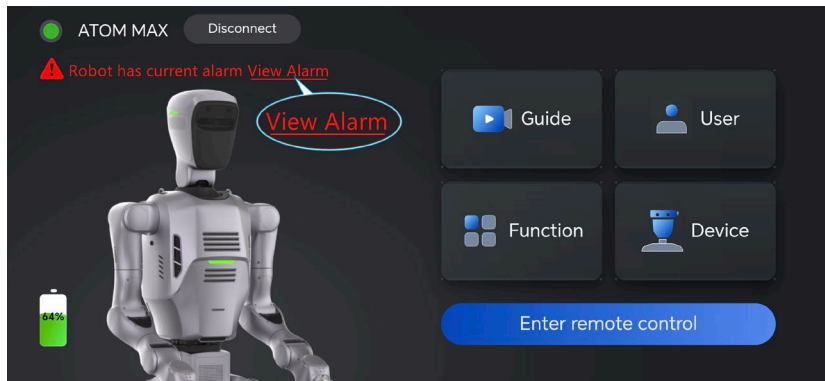
Robot connected (disabled)



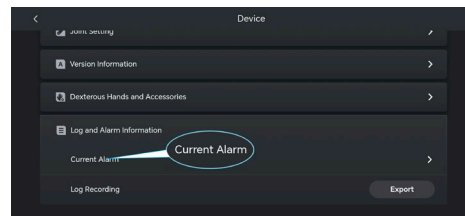
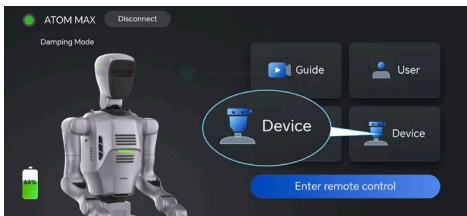
The robot connected (enabled)

4. Check the robot alarm information:

- After successfully connecting to the robot, if any alarms are present, the alarm information will be displayed on the App home page. Tap **View Alarm** to go to the alarm information page.

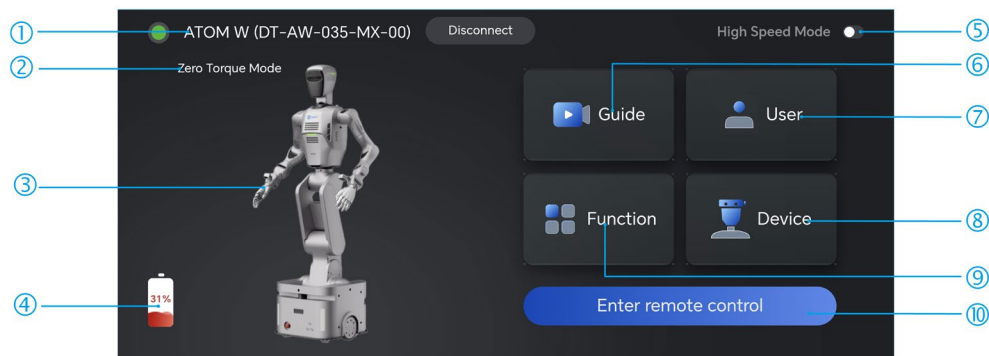


- After successfully connecting to the robot, go to the "Device" page in the App and tap "Current Alarm" to view alarm information.



1.4 App main interface

After successfully installing the App and connecting to the robot, the App main interface appears as follows:



No.	Description
①	Display whether the robot is connected.
②	After a successful connection, the robot status information is displayed, such as emergency stop, error messages, enable status, and the robot's current operating mode.
③	Robot appearance schematic diagram.
④	Display the robot's current battery level.
⑤	(ATOM-W only) Turn high-speed mode on or off. When off, the default speed is 0.5 m/s; when on, the high-speed motion speed is 1.5 m/s.
⑥	Tap to view the built-in operation guide videos (an internet connection is required to watch the videos).
⑦	Switch the App's display language, check the App version, or view the service agreement and privacy policy. For details, refer to Switch interface language .
⑧	- View the device model and software information. For details, refer to Viewing robot data. - View or clear alarm information. For details, refer to Viewing/Clearing alarm. - Export and save the App logs to your phone. For details, refer to Exporting logs. - View the robot mode, joint information, joint limits, release brakes, recalibrate joints, fine-tune joint motors, or perform a full-system auto-check. For details, refer to Joint settings. - Enable the dexterous hand and configure the emergency stop DI. For details, refer to Dexterous hand and accessory settings descriptions.
⑨	View or set official robot actions and record custom actions. For details, refer to the Action library.

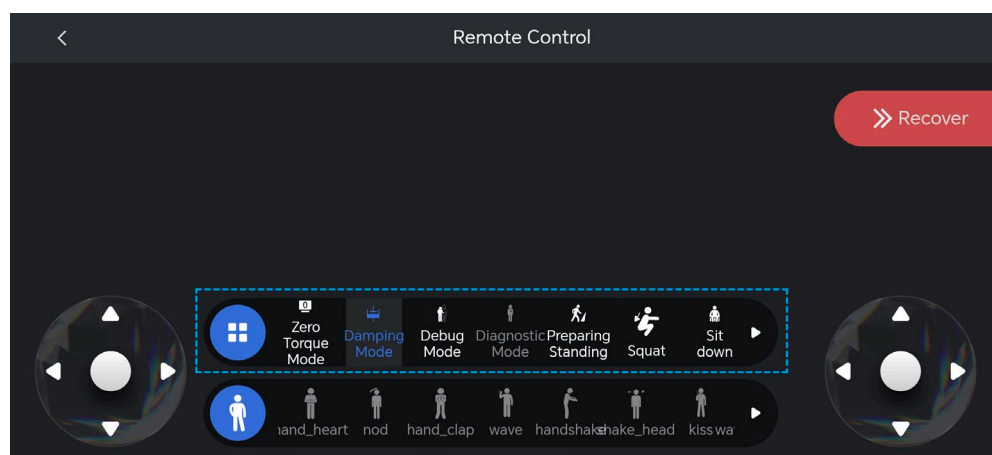
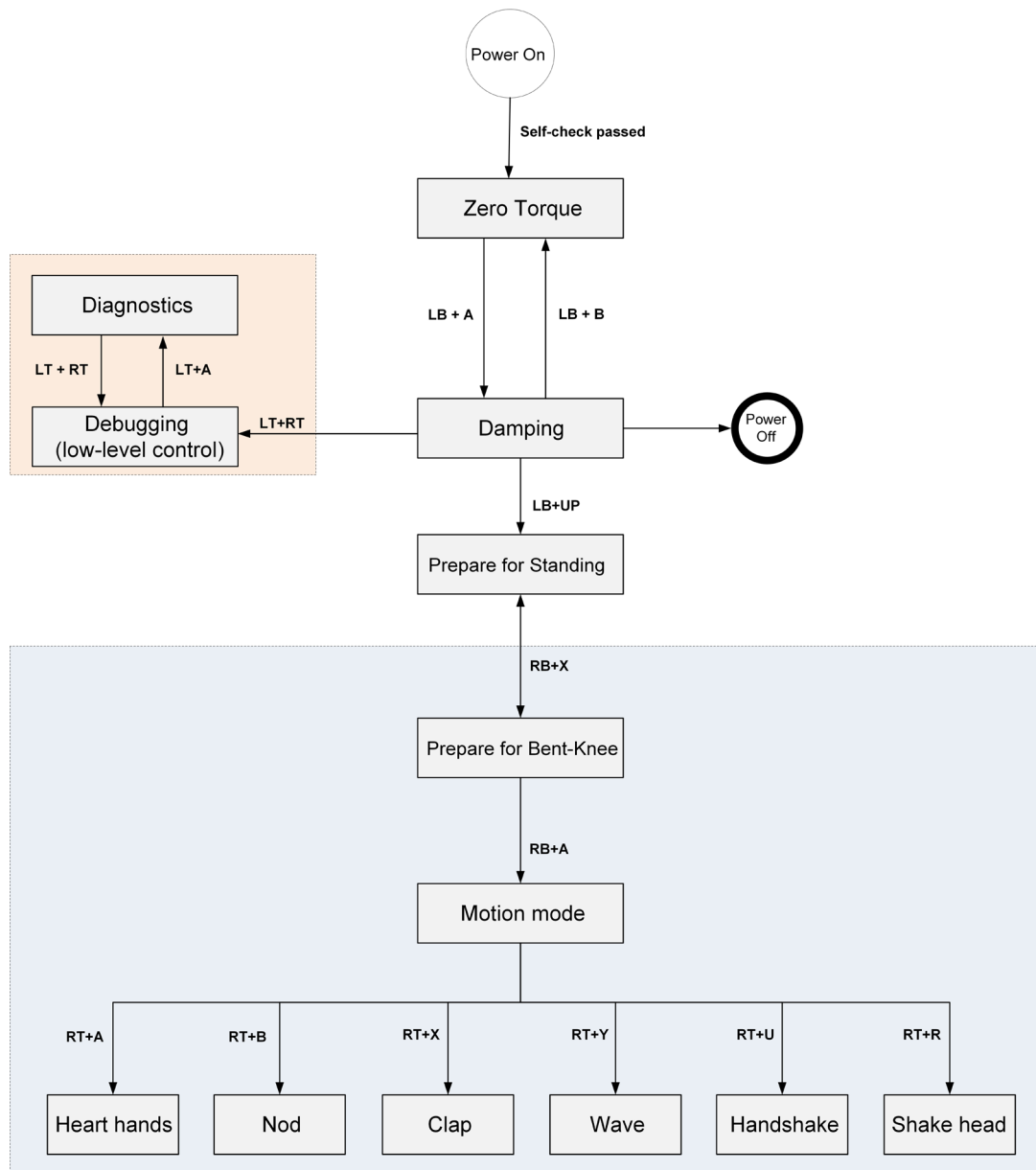
No.	Description
	• Teleoperate to record custom robot actions. For details, refer to Teleoperation. • (ATOM-Max, ATOM-Standard, and ATOM-D only) Configure robot patrol and navigation. For details, refer to Radar navigation. • Configure the voice assistant. For details, refer to Voice assistant. • (ATOM-W and ATOM-D only) Control the coordinates/height of the upper body or lifting axis. For details, refer to Upper body/Lifting axis control.
⑩	Tap Enter remote control to perform emergency stop, move forward/backward/left/right, switch postures, and demonstrate skills.

1.5 App remote control

On the App home page, tap **Enter Remote Control**. On the **Remote Control** page, you can move the robot, switch its modes, and perform skills.

Switch modes

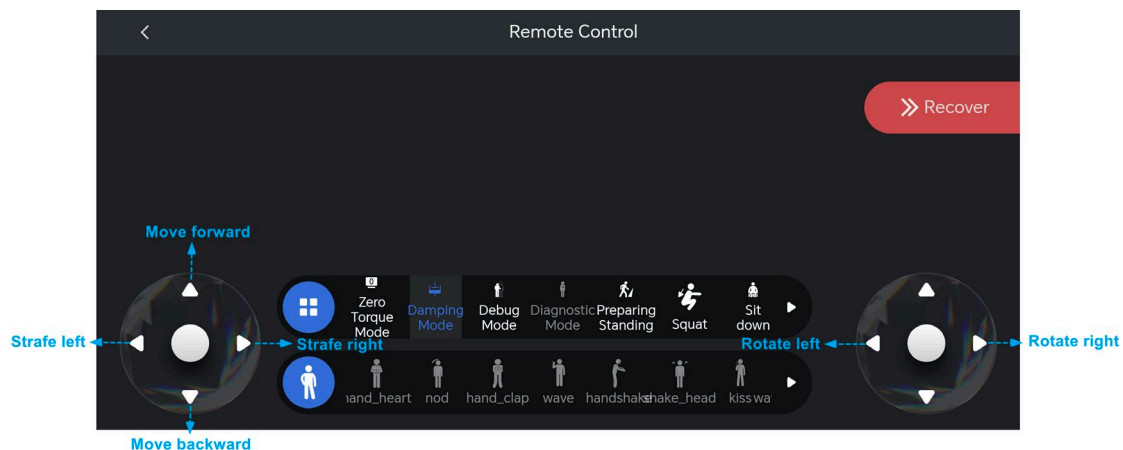
As shown in the flowchart below, switch between different postures by tapping the mode icons on the interface.



Control movement

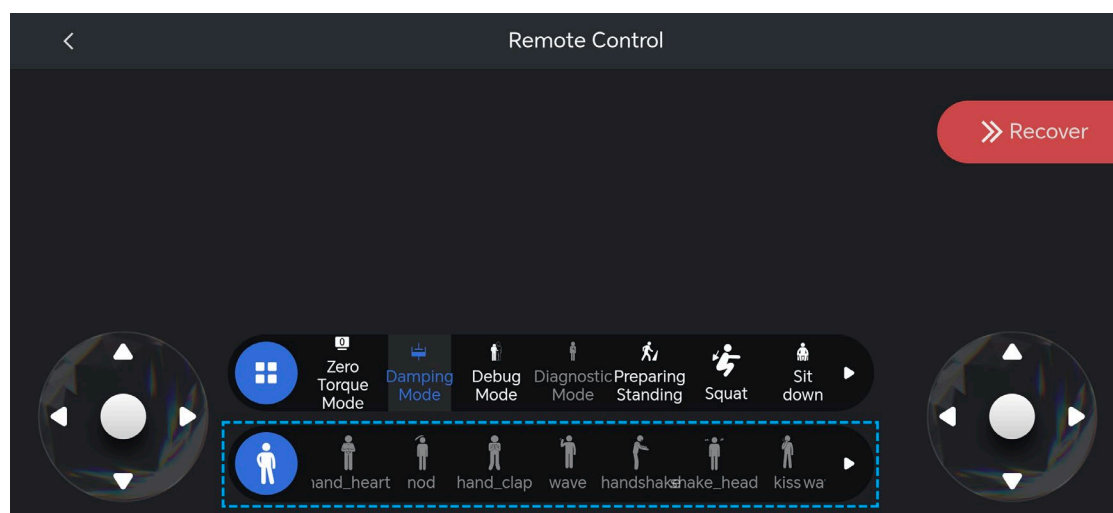
After entering motion control mode via [Switching modes](#), the robot can be controlled to move.

- Slide the dot on the left directional pad ○ Up △ or Down ▽ to move the robot forward or backward.
- Slide the dot on the left directional pad ○ Left ◀ or Right ▶ to strafe the robot left or right.
- Slide the dot on the right directional pad ○ Left ◀ or Right ▶ to rotate the robot left or right.



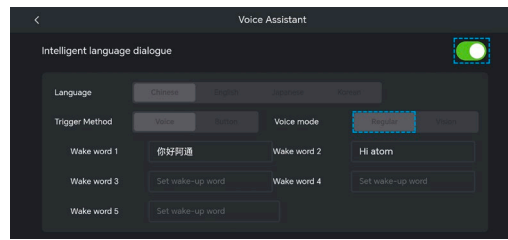
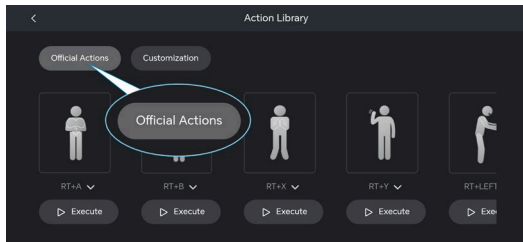
Display skills

After entering motion control mode via [Switch modes](#), tap the skill icons on the interface to display different skills.



1.6 Voice control

After configuring it on the App, you can use voice control to operate the robot. The configuration process is as follows:



- ① Configure preset skills in the [Action library](#).
Skill names in the action library must be clear and distinguishable, for example, "Heart hands", "Wave", etc.
- ② Go to the [Voice assistant](#) interface, select **Regular** as the voice mode, and enable **Intelligent language dialogue**.
- ③ Use the remote controller or [App remote control](#) to switch the robot mode to "Motion Mode".
- ④ Wake up the voice control function and talk to the robot according to the settings in the Action Library.

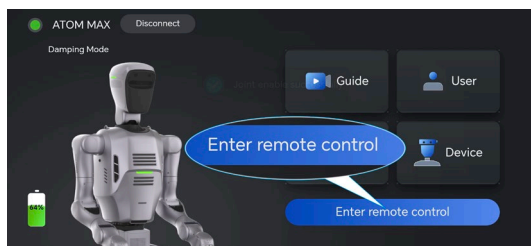
NOTICE

Currently, each round of conversation supports triggering only one action, not multiple actions.

1.7 Robot emergency stop

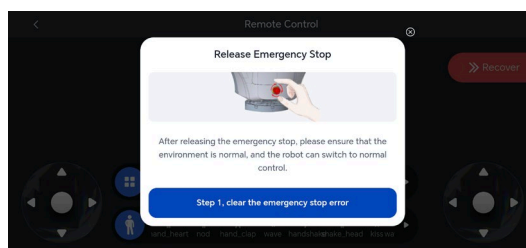
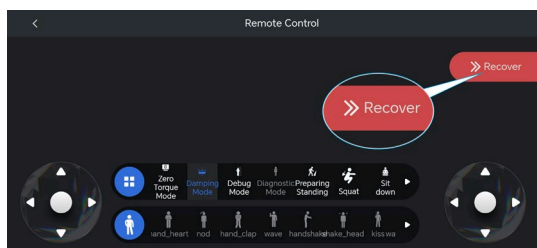
In the event of an unexpected situation during robot operation, you can initiate an emergency stop using the App. Before operation, please take care to protect the robot to avoid accidental damage.

Emergency stop operation

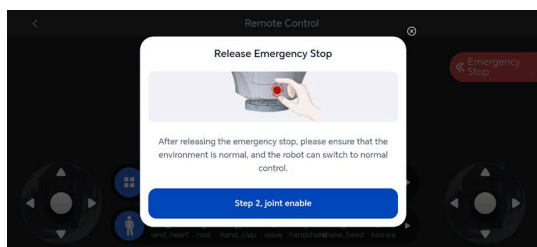


- ① After connecting to the robot, tap "Enter remote control".
- ② Slide the "Emergency Stop" button to the left to trigger the robot's emergency stop. At this point, the E-Stop button changes to a "Recover" button.

Recovery after emergency stop



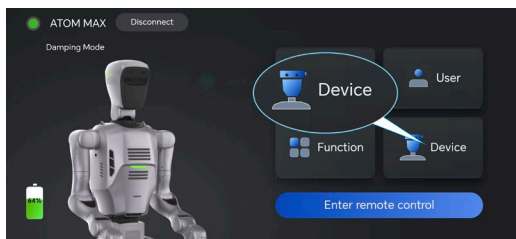
- ① After the issue is resolved, go to the "Enter remote control" page in the App, slide the "Recover" button to the right.
- ② Follow the App prompts to release the emergency stop status first.



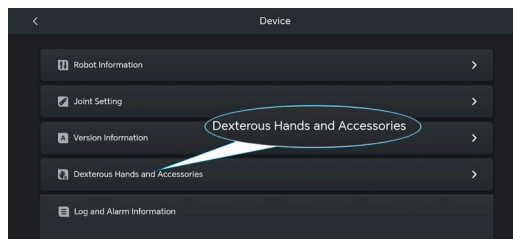
- ③ Follow the App prompts to re-enable the joints.

2. Device Settings

2.1 Dexterous hands and accessory settings



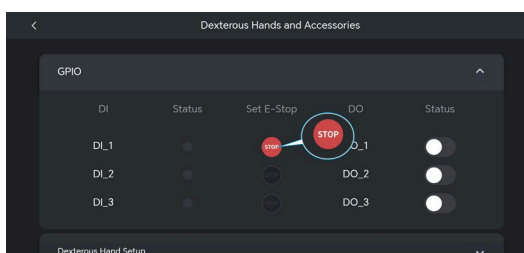
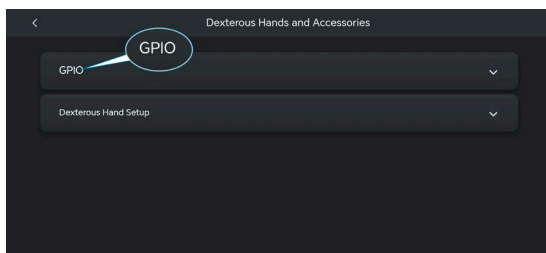
- ① After connecting to the robot, tap "Device".



- ② Tap "Dexterous Hands and Accessories".

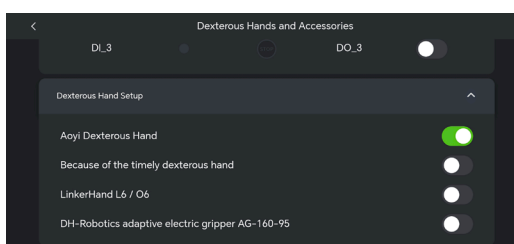
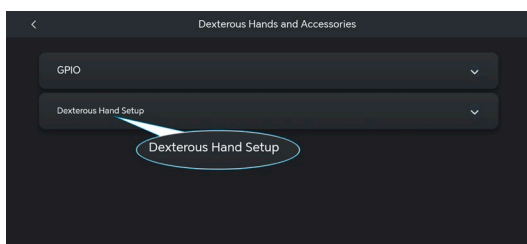
2.1.1 GPIO settings

When an external emergency stop button is connected to the robot, go to the **GPIO** page and set the DI connected to the emergency stop button as the emergency stop (tap the STOP icon; it changes from gray to red, indicating that the DI has been set as the emergency stop input).



2.1.2 Dexterous hand settings

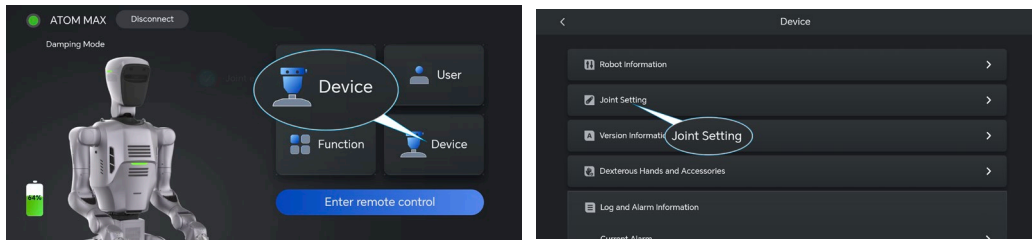
Based on the actual dexterous hand/gripper model used with the robot, turn on the corresponding switch on the **Dexterous Hand Settings** page to enable it (only one dexterous hand/gripper can be enabled at a time).



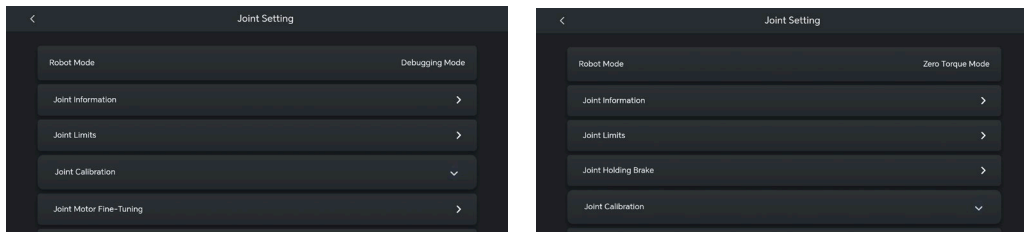
NOTICE

Currently, two dexterous hands or one gripper are supported: the OYMotion dexterous hand, the LinkerBot dexterous hand, or the DH-Robotics adaptive gripper. Different users may have different brands of dexterous hands. Please configure the brand of dexterous hand or gripper according to the actual product. If the actual brand does not match the settings, the dexterous hand will not operate.

2.2 Joint settings



- ① After connecting to the robot, tap "Device".
- ② Tap "Joint Settings".



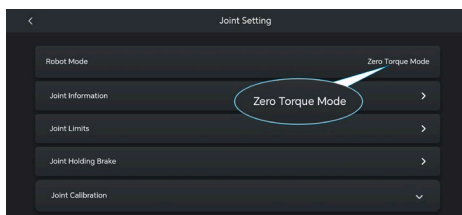
- ③ You can view the robot mode, joint information, and joint limit data. Reconfigure joint limits, release brakes (ATOM-W only), calibrate joints, fine-tune joint motors, or perform a full-system auto-check.

2.2.1 Robot mode

NOTICE

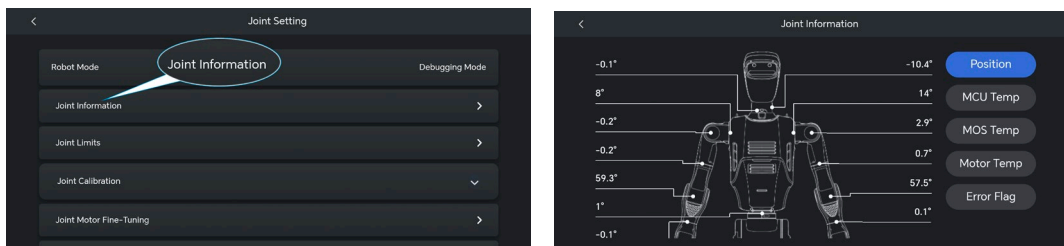
The ATOM-D robot does not support mode switching.

Display the current robot mode. The available modes are:



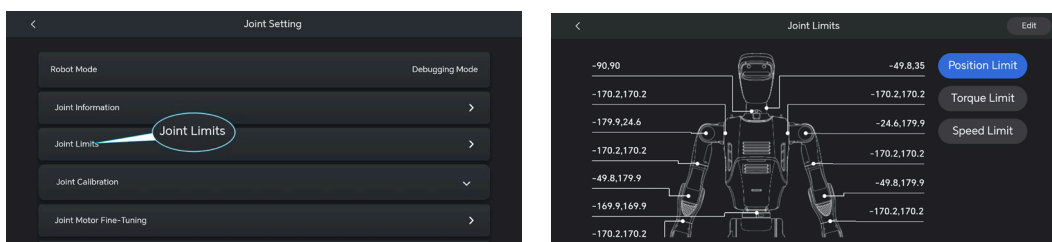
- **ATOM-Max, ATOM-Standard:** Zero Torque Mode, Damping Mode, Debug Mode, Diagnostic Mode, Standing Preparation Mode, Knee-Bent Walking Mode, and Upper-limb Control Mode.
- **ATOM-W:** Zero Torque Mode, Damping Mode, Debug Mode, Diagnostic Mode, Ready Mode, Pack Mode, Stand Mode, and Motion Mode.

2.2.2 Joint information

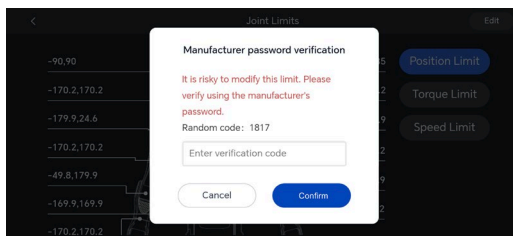


- ① On the "Joint Settings" page, tap "Joint Information".
- ② Switch to temperature and error flags.

2.2.3 Joint limits



- ① On the "Joint Settings" page, tap "Joint Limits".
- ② Switch to different tabs to view the position limits, torque limits, and speed limits of each joint.

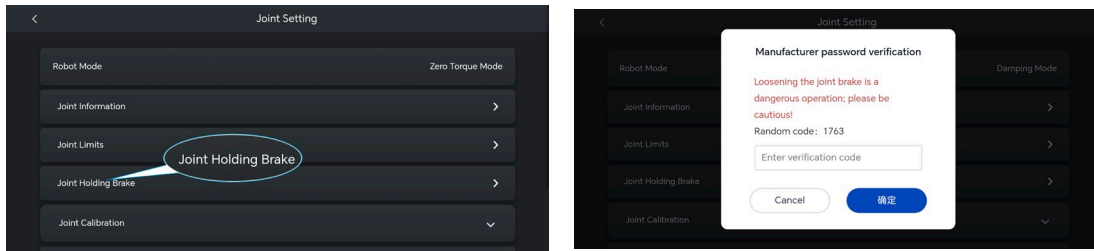


- ③ Tap the "Edit" button in the upper right corner of "Joint Limits" to open the manufacturer password verification window. Modifying limits carries operational risks and must only be done under the guidance of technical support.

2.2.4 Joint brakes (ATOM-W only)

NOTICE

Joint brake settings are available only for the lower limbs of the ATOM-W wheeled humanoid robot.

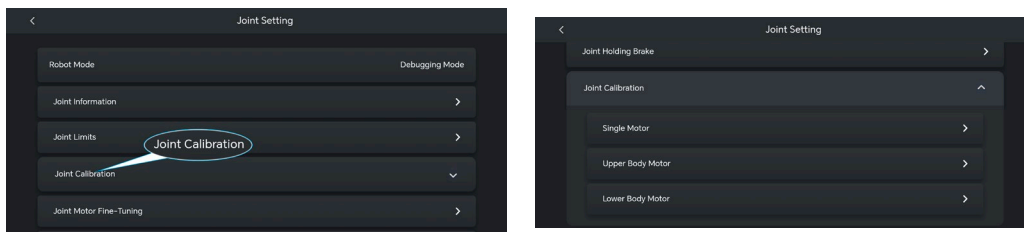


- ① On the "Joint Settings" page, tap "Joint Brakes".
- ② A manufacturer password verification window will pop up. Releasing the joint brakes is a hazardous operation. Please be careful! This must be performed under the guidance of technical support.

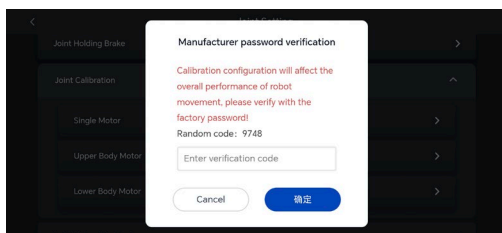
2.2.5 Joint calibration

NOTICE

Zero-point calibration has been completed at the factory. Please do not recalibrate the joints during normal operation.

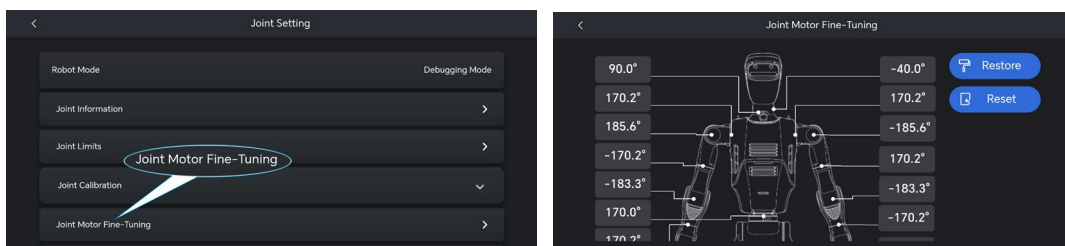


- ① On the "Joint Settings" page, tap "Joint Calibration".
- ② Calibration can be performed on the IMU, single motor, all motors, and encoders.



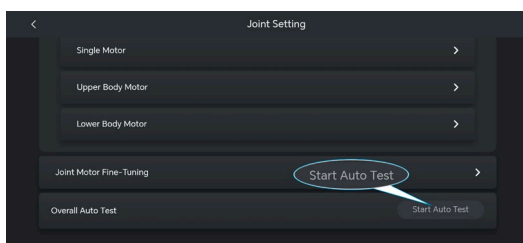
- ③ Tap any submenu under Joint Calibration, and a manufacturer password verification window will pop up. Recalibration may affect the overall motion performance of the robot and must be performed under the guidance of technical support.

2.2.6 Joint motor fine-tuning



- ① On the "Joint Settings" page, tap "Joint Motor Fine-Tuning".
- ② Tap "Restore" to revert the current joint motor values to the last modified values; tap "Reset" to reset them to the factory default values.

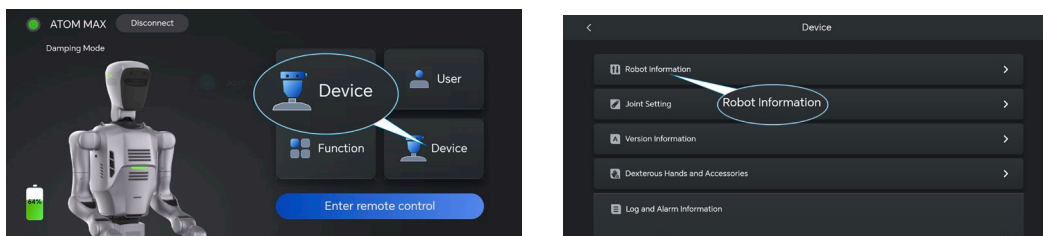
2.2.7 Overall auto test



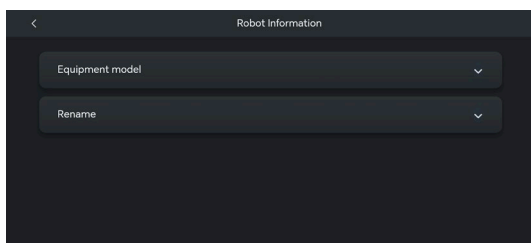
On the **Joint Settings** page, tap **Start Auto Test** to perform an automatic full-system inspection.

2.3 View robot data

2.3.1 Robot information

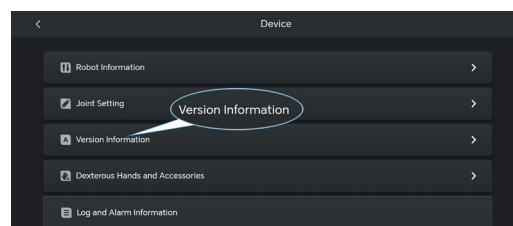
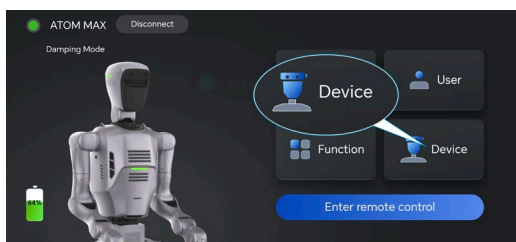


- ① After connecting to the robot, tap "Device".
- ② Tap "Robot Information".

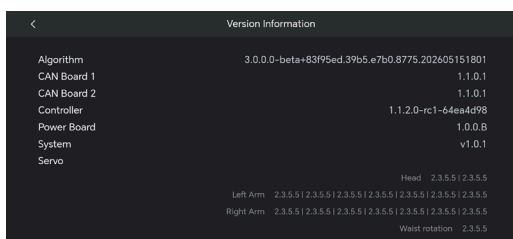


- ③ You can view the device model or rename the device.

2.3.2 Software information

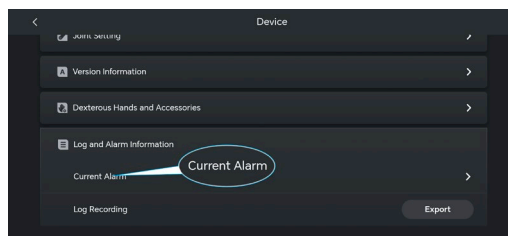
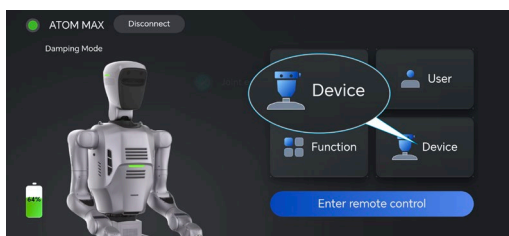


- ① After connecting to the robot, tap "Device".
- ② Tap "Version Information".

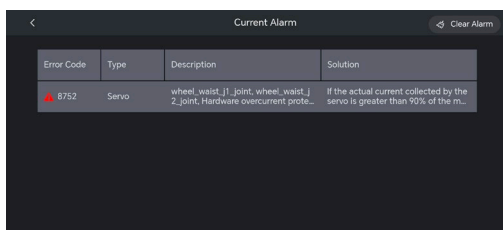


- ③ View version information for the robot's algorithms, main/backup battery, CAN board, controller, power board, system, and servo.

2.4 View/Clear alarm

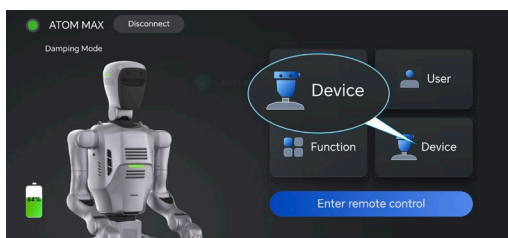


- ① After connecting to the robot, tap "Device".
- ② Scroll down on the current page and tap "Current Alarm".

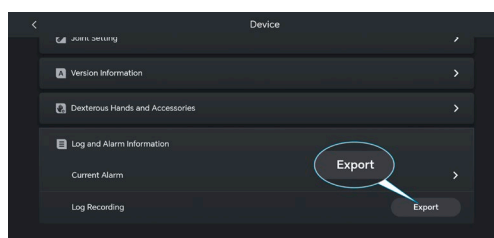


- ③ View the current alarm information, and tap **Clear Alarm** in the upper-right corner of the page to clear the alarm messages.

2.5 Export logs

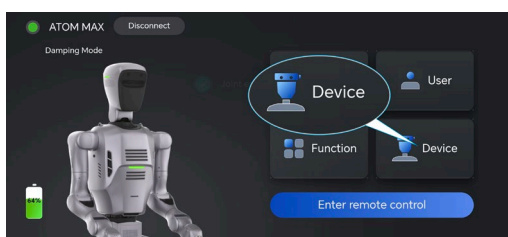


- ① After connecting to the robot, tap "Device".

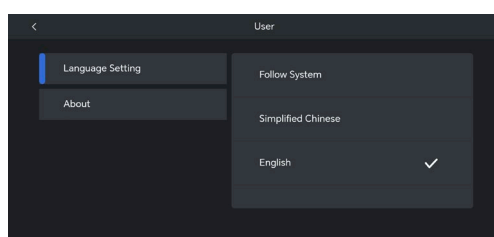


- ② Tap the "Export" button to export all logs saved by the App to your phone.

2.6 Switch the interface language

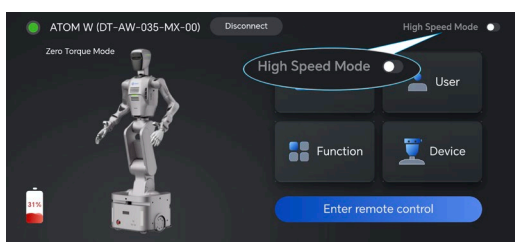


- ① After connecting to the robot, tap "User".

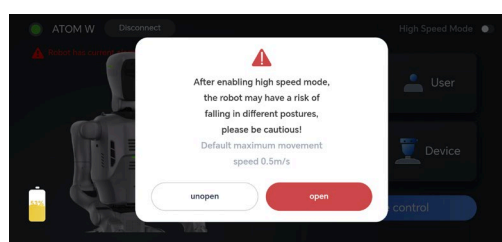


- ② On the "Language Settings" tab, set the App interface language to Simplified Chinese or English (default follows system language).

2.7 High-speed mode (ATOM-W only)



- ① After connecting to the robot, the App automatically syncs the robot's mode. If the robot is currently in High-Speed Mode, it will be shown as enabled ; if not, you can tap "High-Speed Mode" to enable it.

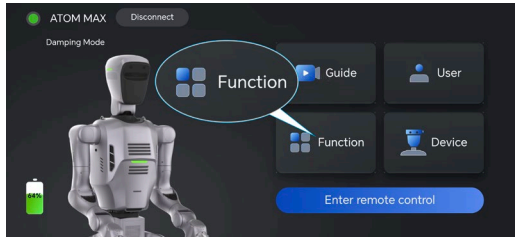


- ② Tap "Open" in the pop-up prompt. Once enabled, the robot enters High-Speed Mode with a motion speed of 1.5 m/s.

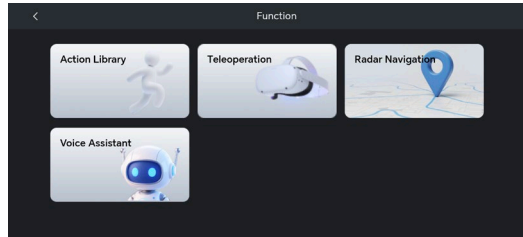
3. Robot Function

3.1 Action library

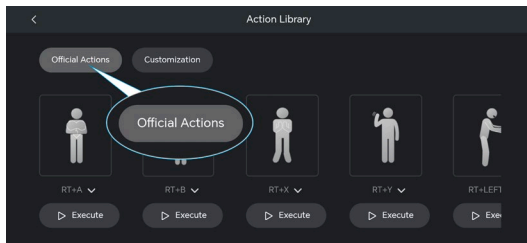
3.1.1 Official actions



- ① After connecting to the robot, tap "Function".

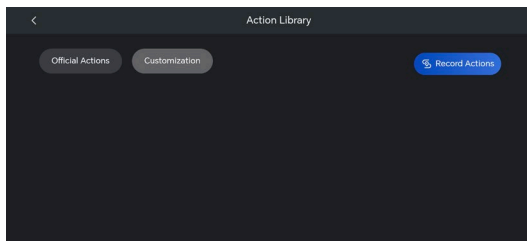


- ② Tap "Action Library".

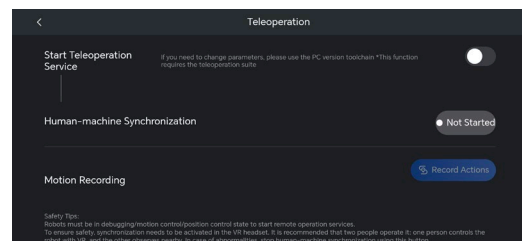


- ③ On the "Official Actions" page, you can view or perform official actions, and also reconfigure the remote controller key combinations for triggering actions.

3.1.2 Custom actions

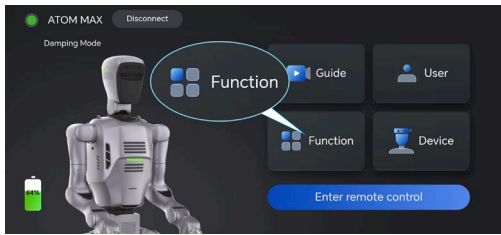


- ① Switch to the "Custom" page, where you can modify the remote controller key combinations for custom actions, perform or delete custom actions; you can also tap "Record Actions" to enter the teleoperation page.

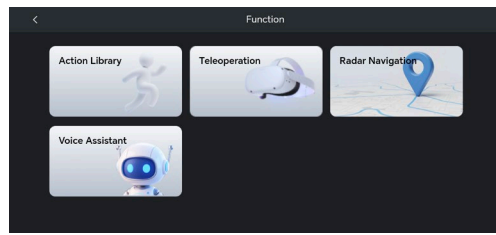


- ② For instructions on recording custom actions via teleoperation, refer to [Teleoperation](#).

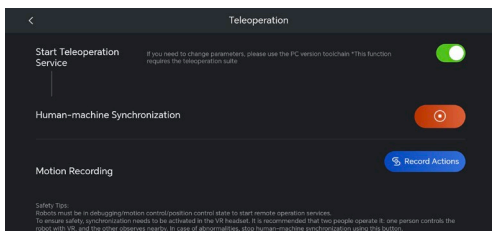
3.2 Teleoperation



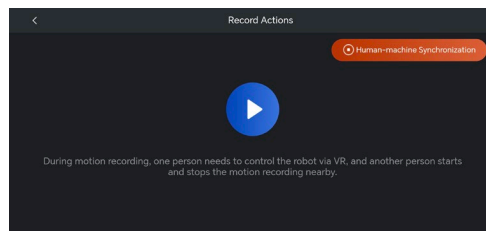
- ① After connecting to the robot, tap "Function".



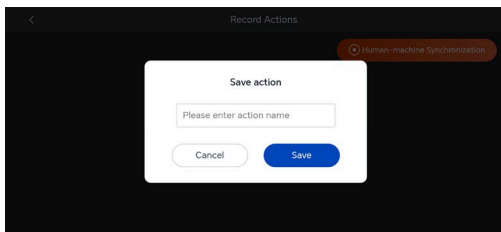
- ② Tap **Teleoperation** to enter the teleoperation interface. You can also enter the teleoperation interface from the [Custom action](#) page.



- ③ After starting the teleoperation service and enabling human-robot synchronization, tap **Record Actions** to enter the recording page.



- ④ To start recording, one person controls the robot via VR while another person starts and stops the action recording on the side.



- ⑤ After recording, save the action.

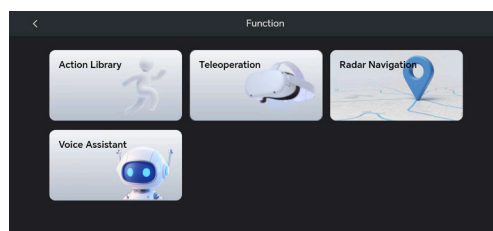
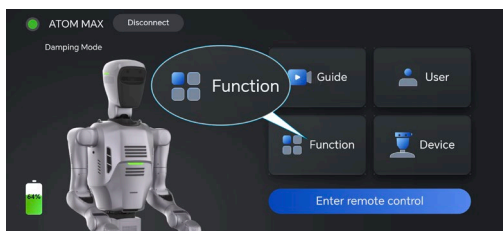
NOTICE

- To modify teleoperation parameters, please use the PC tool (which requires the teleoperation suite).
- The teleoperation service can only be started when the robot is in Debug, Motion Control, or Position Control mode.
- For safety, enable human-robot synchronization in the VR headset. It is recommended that two people perform the operation: one controls the robot via VR, and the other monitors from the side and stops the human-robot synchronization immediately if any abnormality is detected.
- For detailed instructions on teleoperation, please refer to the *DOBOT ATOM Series Robot SDK Application Development Guide*.

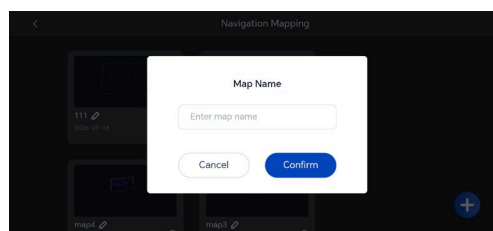
3.3 Radar navigation (ATOM-Max, ATOM-Standard, ATOM-D)

Through the "Radar Navigation" feature in the App, you can create new maps and road networks, enabling the robot to perform single or multiple patrols along fixed routes, or patrol a single point.

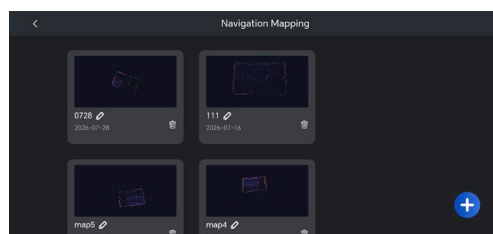
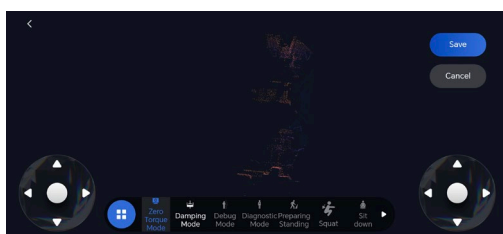
3.3.1 New map



- ① After connecting to the robot, tap "Function".
- ② Tap "Radar Navigation".

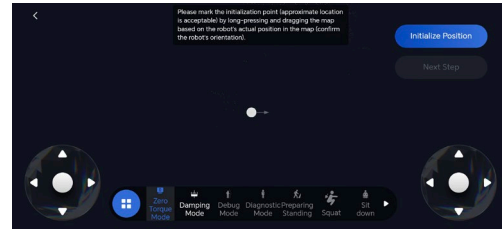
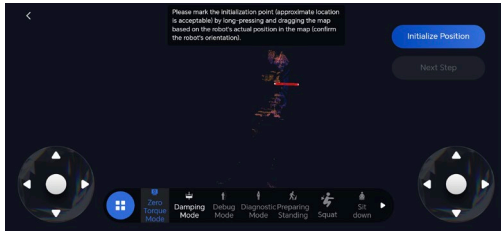


- ③ Tap  in the lower-right corner to create a new map.
- ④ Enter a map name and tap "Confirm" to enter the mapping page.

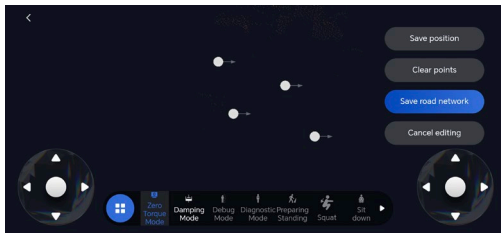


- ⑤ Acquire point cloud data and render the point cloud map. Tap **Save** in the upper-right corner to complete mapping and automatically return to the map list page.
- ⑥ You can create multiple maps, as well as rename or delete them.

3.3.2 Creat a new road network



- ① Tap to enter an existing map.
- ② Long-press on the map to place a marker, tap "Initialize Position", and then tap "Next" to create a new road network.

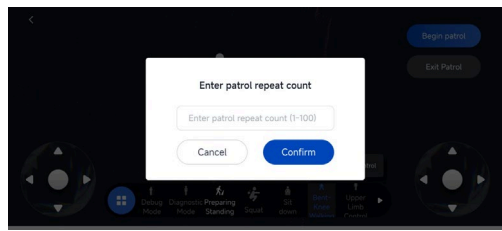


- ③ Long-press on the map to place markers (multiple markers can be set), and tap **Save road network**.
- ④ Added markers will be connected automatically. You can then edit the road network or start patrol navigation.

3.3.3 Patrol navigation



- ① Tap "Patrol navigation".
- ② Tap the points to be patrolled one by one. The points will be automatically connected in the order they are tapped.



- ③ Tap "Begin patrol".
- ④ Enter the number of patrol cycles (1 to 100 repetitions supported). Tap "Confirm".

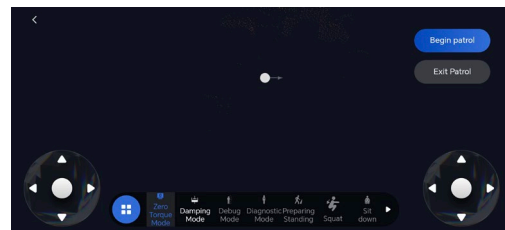


- ⑤ During patrol navigation, the robot's real-time position, yaw angle, patrol time, and task progress will be displayed on the right side. You can pause or stop the patrol navigation.

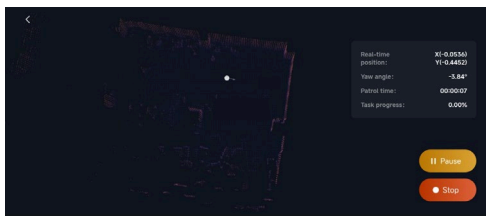
3.3.4 Single-point navigation



- ① Tap "Single-point navigation".



- ② Tap the target point, then tap "Begin Patrol".



- ③ During single-point navigation, the robot's real-time position, yaw angle, patrol time, and task progress will be displayed on the right side. You can pause or stop the single-point navigation.

3.4 Voice assistant

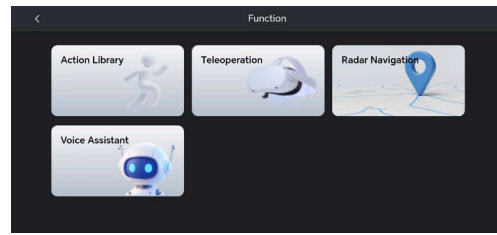
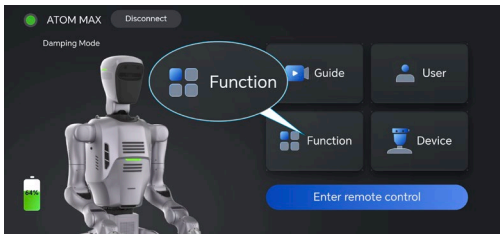
The voice assistant supports a local mode, allowing you to feed your own knowledge base into the built-in language model for scenario-specific conversations.

NOTICE

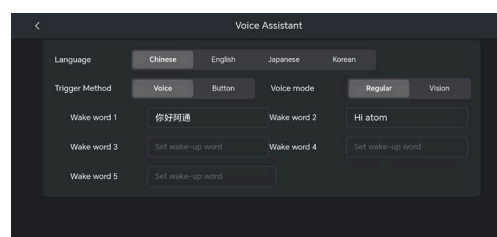
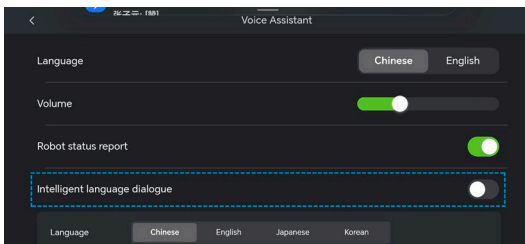
Voice assistant is supported only on the ATOM-Max and ATOM-W robots.

Enable/Disable the voice assistant

The ATOM's Voice Assistant feature is disabled by default. Please connect the robot to the App first, then follow the steps below to enable it.



- ① After connecting to the robot, tap "Function".
- ② Tap "Voice Assistant".



- ③ Enable "Intelligent language dialogue". Other options on the current page are described as follows:

- **Language:** Set the robot's speaking language to Chinese or English.
- **Volume:** Adjust the robot's speaking and conversation volume.
- **Robot status report:** Enable or disable voice feedback when the robot's status or mode changes.
- **Language:** The language used for human-robot voice conversations. Currently supports Chinese, English, Japanese, and Korean.
- **Trigger Method:** Ways to initiate voice conversation with the robot, including voice wake-up and button trigger. For details, refer to [Trigger method](#).
- **Wake Word:** When the conversation trigger method is set to **Voice**, you need to set a wake word. Up to 6 wake words are supported.
- **Voice Mode:** Supports standard conversation and vision-based conversation. Visual conversation means the robot replies based on the scene observed by its head camera and the questions asked.

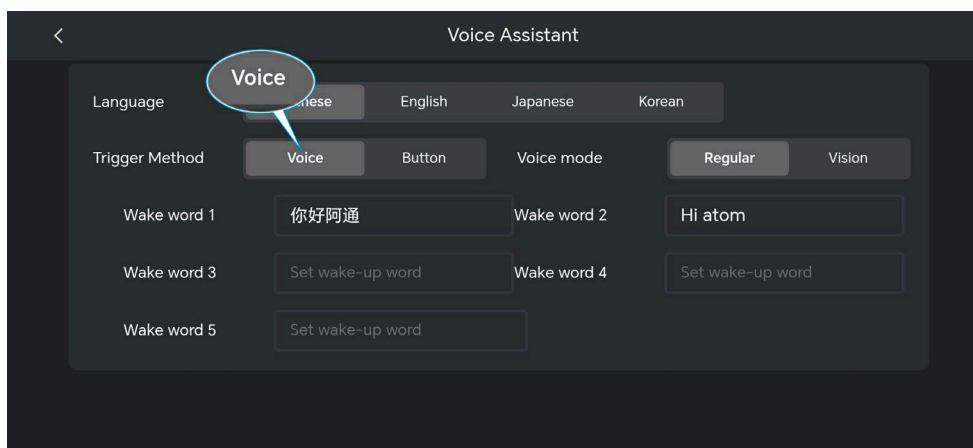


NOTICE

Only after disabling "Intelligent language dialogue" can you modify the conversation language, conversation trigger method, voice mode, and wake word.

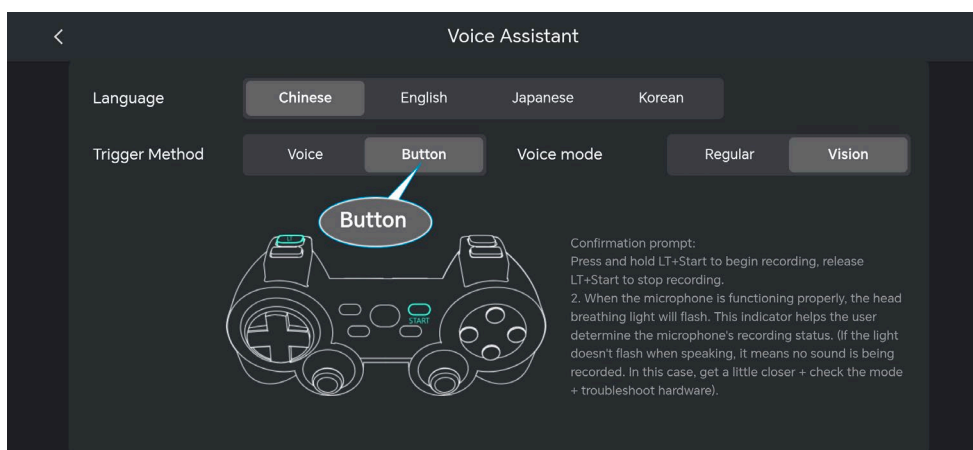
Trigger method

• Voice-triggered

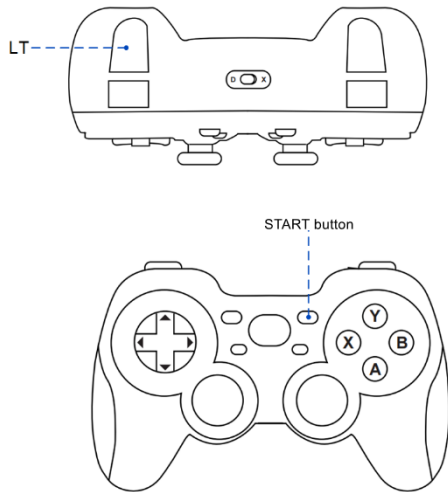


Wake word	The default wake word is "Hi atom" and can be customized.
Feature	Once woken up, it supports multi-turn natural conversations, suitable for quiet, everyday dialogue scenarios.
Description	After successful wake-up using the wake word, the robot will respond, and you can then engage in unlimited multi-turn free conversations. The conversation ends after 15 seconds of silence. You need to wake the robot up again (up to 6 wake words can be set in the App).

• Button-triggered



Feature	Forces a single voice recognition, suitable for noisy environments.
Description	No wake word is needed. Press and hold the LT + START buttons on the remote controller (as shown in the figure below) to start recording, and release them to stop recording. The sound captured during this stage will be forcibly recognized and sent to the speech recognition framework.



Tips for improving speech recognition success rate

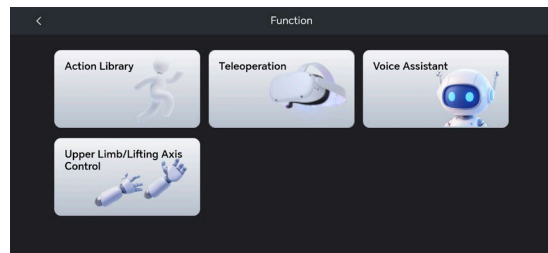
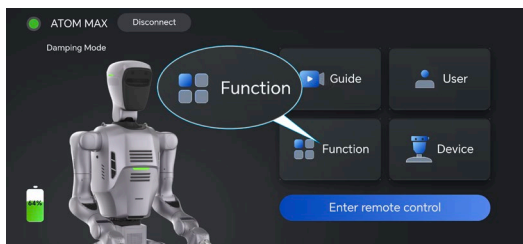
Stand directly in front of the robot (facing the microphone openings) within 1 meter when speaking.

3.5 Upper limb/Lift axis control (ATOM-W and ATOM-D only)

NOTICE

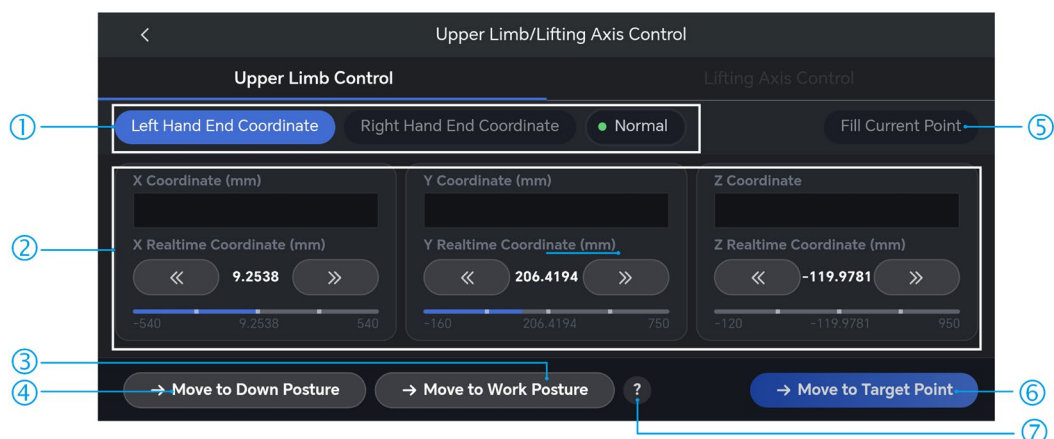
The ATOM-W wheeled humanoid robot supports end position control and lift axis control, while the ATOM-D robot supports end position control only.

After connecting to the robot, the App automatically syncs the robot's mode. If the robot is currently in **Precision Position** mode, the App will directly enter the **Upper Limb/Lifting Axis Control** page. If not, follow the steps below to enter the Upper Limb/Lifting Axis page.



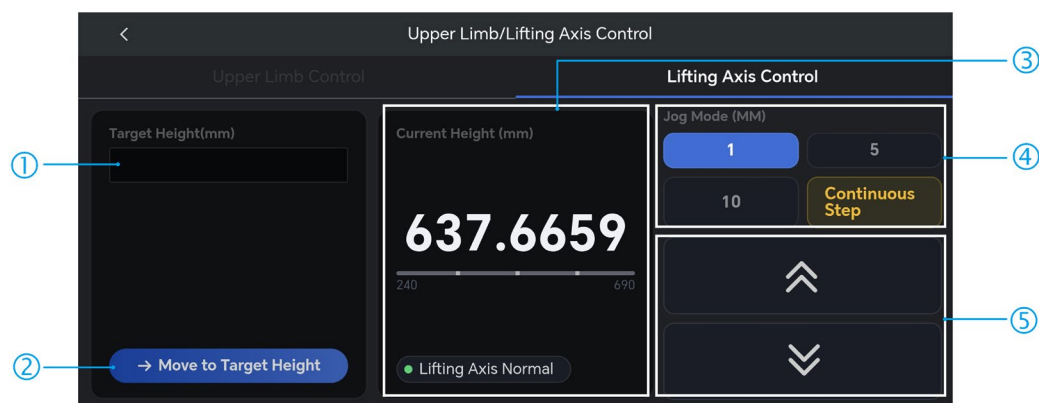
- ① After connecting to the robot, tap "Function".
- ② Tap "Upper Limb/Lifting Axis Control". The interface will prompt you to switch to Precision Position Mode. Tap **Safety Confirmed, Switch** to enter the Upper Body/Lifting Axis interface.

3.5.1 End position control



No.	Description
①	You can set the left and right end coordinates separately, and the status of each end will be displayed. When the end status is abnormal, a status alarm and pop-up prompt will be displayed. After you clear the alarm as prompted, the status will return to normal.
②	Set the target coordinate values (X, Y, Z, Rx, Ry, Rz) for the hand end, and display the current real-time coordinates and coordinate range values. - Long press << to decrease the coordinate values of the current position. - long press >> to increase the coordinate values of the current position.
③	Long press "Move to Down Posture" and the robot arm will move to the specified position; if you release the long press during movement, the arm will still continue to move to the hanging posture.
④	Long press "Move to Work Posture" to move the robot arm to the specified position; if you release the long press during movement, the arm will stop moving.
⑤	Tap "Fill Current Point" to display the robot arm's current coordinates in the X, Y, Z, Rx, Ry, and Rz fields.
⑥	Long press "Move to Target Point" to send the robot to the target coordinates.
⑦	Tap "?" to display the coordinate reference, hanging posture, and working posture.

3.5.2 Wheeled lift axis control



No.	Description
①	Set the target height of the lift axis.
②	Long press "Move to Target Height" to move the wheeled lower limbs to the set target height.
③	Display the lift axis current height, height range, and lift axis status. When a lifting axis status error occurs, a status alarm and a pop-up prompt will appear. After clearing the alarm as prompted, the status will return to normal.
④	Set the step range for jog mode: 1mm, 5mm, 10mm, and continuous step.
⑤	- Long press ⤴ to raise the lift axis by the selected step range. - Long press ⤵ to lower the lift axis by the selected step range.