a) receiving a series of programming inputs from a user at the user device;
b) receiving a set of sensor measurements from the remote toy robot;
c) automatically generating a set of control instructions based on the set of sensor measurements and an unperformed programming input of the series;
d) sending the set of control instructions to the toy robot, wherein the toy robot is operated based on the set of control instructions; and
e) iteratively repeating b) to d) for successive programming inputs based on subsequent sets of sensor measurements received from the toy robot, wherein the subsequent sets of sensor measurements are recorded during toy robot operation based on a previous set of control instructions.

20. The method of claim 19, further comprising monitoring toy robot performance of the previous set of control instructions based on the subsequent set of sensor measurements received from the toy robot, comprising:

- performing e) in response to the toy robot performing the previous set of control instructions within a threshold degree of error;
- identifying an inconsistency between the subsequent set of sensor measurements and a requirement for a successive set of control instructions; and
- in response to identification of an inconsistency:
  - determining a secondary programming input based on the subsequent set of sensor measurements;
  - displaying a virtual representation of the secondary programming input;
  - receiving a selection of the secondary programming input;
  - replacing the successive programming component with the secondary programming input; and
  - performing b) using the secondary programming input as the unperformed programming component of the series.