WHAT IS CLAIMED IS:

1. A robotic system comprises:

a first component comprising a first processor and a first connector;

a second component comprising a second processor and a second connector; and

a skin connector configured to couple the first component and/or the second component to attach a shaped cover;

wherein the first connector of the first component is connectable to the second connector of the second component in a desired orientation relative to one another, wherein the first processor and the second processor are configured to communicate with one other when connected in the desired orientation.

2. The robotic system according to claim 1, wherein the skin connector comprises:

a ridge configured to insert in a groove element of the robotic system; and

one or more snap elements formed at edges of the skin connector, the one or more snap elements configured to be snap fit in a cavity of a shaped cover thereby giving the robotic system a desired toy form.

3. The robotic system according to claim 2, wherein the one or more snap elements project perpendicular to a first face of the skin connector in a first direction, the first direction being opposite to a projecting direction of the ridge.

4. The robotic system according to claim 3, wherein the one or more snap elements are a cantilever type of elements.

5. The robotic system according to claim 3, wherein a body of the skin connector has a substantially rectangular or square shaped.

6. The robotic system according to claim 5, wherein the body includes a raised portion, the raised portion being raised with respect to the first face, and wherein the raised portion includes a hollow portion in which the ridge is formed.

7. The robotic system of claim 1, wherein the first connector comprises a groove; and the second connector comprises a ridge corresponding to the groove, the ridge comprising a plurality of electrical

contacts, wherein the groove is configured to receive the ridge and the plurality of electrical contacts in a plurality of orientations.

8. The robotic system of claim 7, wherein the first connector further comprises a track element having a plurality of tracks corresponding to the plurality of contacts of the second connector, wherein the track element is located at a first side of the first connector and receives the plurality of the contacts of the second connector from a second side of the first connector, the second side being opposite to the first side.

9. The robotic system of claim 8, wherein the first connector comprising the track element is included in a first housing and the second connector is included in a second housing.

10. The robotic system of claim 9, wherein the groove of the first housing is an X-shaped depressed portion depressed inward relative to a face of the first housing, and the ridge is an X-shaped protruding portion protruding outward relative to a face of the second housing, the X-shape of the ridge corresponds to the X-shape of the groove.

11. The robotic system of claim 9, wherein the second housing is at least one of:

a drive motor comprising a first motor configured to receive, via the second connector, a control signal from the first processor of the first housing;

a function motor comprising a second motor configured to receive, via the second connector, another control signal from the first processor of the first housing;

a display comprising a screen configured to receive, via the second connector, information from the first processor of the first housing; and

a sensor configured to generate an output signal corresponding to a characteristic to be measured and send, via the second connector, the output signal to the first processor of the first housing.

12. The robotic system of claim 11, wherein the first processor is further configured to:

identify the second housing and an orientation of the plurality of the orientations of the second housing relative to the first housing based on an address of the second housing and the orientation; and

articulate the second housing, wherein the identified second housing is the drive motor or the function motor.

13. A robotic system comprises:

a first interlocking toy system comprising:

a plurality of pieces configured to interlock with each other via a first interlocking mechanism;

a second interlocking toy system having a second interlocking mechanism comprising:

a first component comprising a first processor, and

a second component comprising a second processor, the second component interoperably connected to the first component, and wherein the first processor communicates with the second processor to send receive control signals or sensor signal therebetween; and

an interface configured to couple, via the second interlocking mechanism at one face, the first component and/or the second component , and couple, via the first interlocking mechanism at another face, at least one piece of the plurality of pieces of the first interlocking toy system at another face to allow interoperability between the first interlocking toy system and the second interlocking toy system.

14. The robotic system according to claim 13, wherein the interface comprises:

a plurality of connecting elements, formed on a first face, having a first geometric configuration compatible with one or more pieces of a first interlocking toy system; and

a joinery, formed on a second face, having a second geometric configuration compatible with the second interlocking toy system, the interface enabling an interoperable connection between the first interlocking toy system and the second interlocking toy system.

15. The robotic system according to claim 14, wherein the plurality of connecting elements are studs and/or stud receptacles arranged in the first geometric configuration.

16. The robotic system according to claim 15, wherein the plurality of connecting elements have geometric configuration compatible with the studs and/or stud receptacles of the one or more pieces of the first interlocking toy system.

17. The robotic system according to claim 14, wherein the joinery includes an X-shaped ridge or an X-shaped groove arranged in the second geometric configuration.

18. A method for configuring a robotic module comprising a processor, the method comprising:

connecting the robotic module to a first housing; and

assigning, via the processor, an identifier to the robotic module, wherein the identifier is configured to identify a type of the robotic module, a number of the robotic module, and/or a location of the robotic module with respect to the first housing.

19. The method of claim 18, wherein the assigning of the identifier comprises:

assigning a first set of bits of a plurality of bits to identify the type of the robotic module, and a second set of bits of the plurality of bits to indicate the number a particular component.

20. The method of claim 19, wherein the assigning of the identifier comprises:

daisy chaining of the plurality of bits corresponding to a plurality of robotic modules connected to the first housing and/or a robotic module of the plurality of robotic modules.