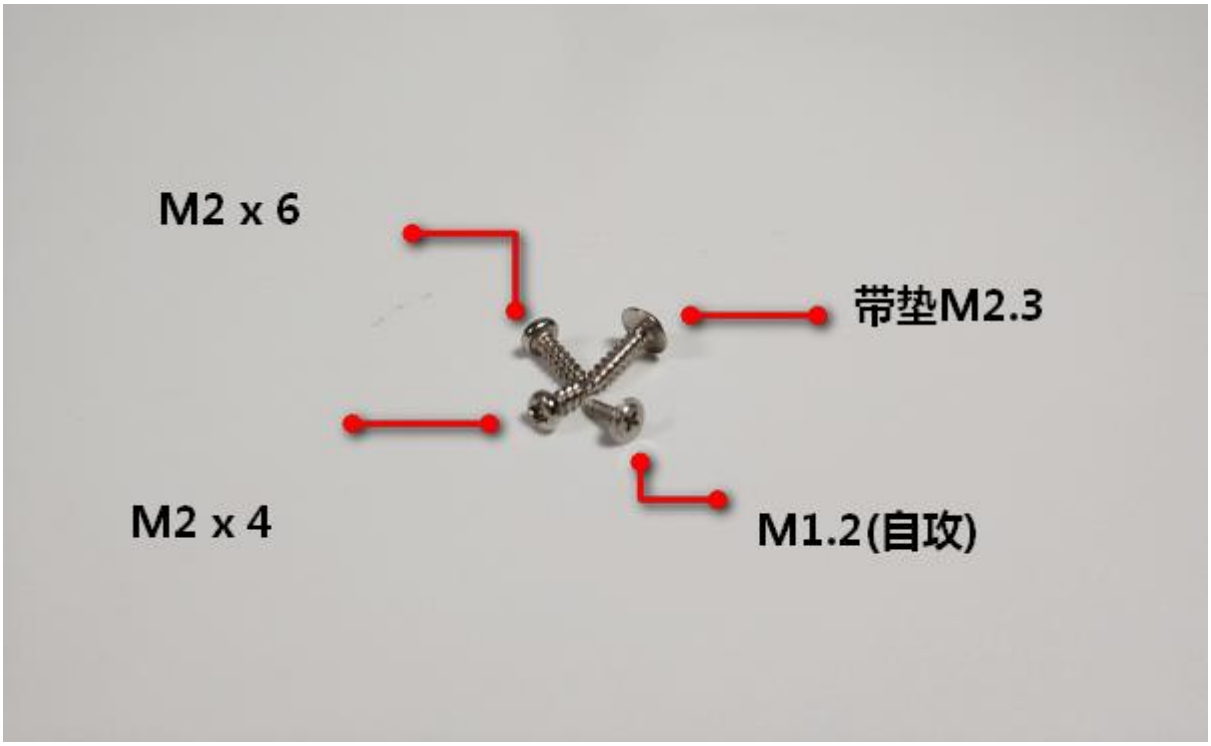
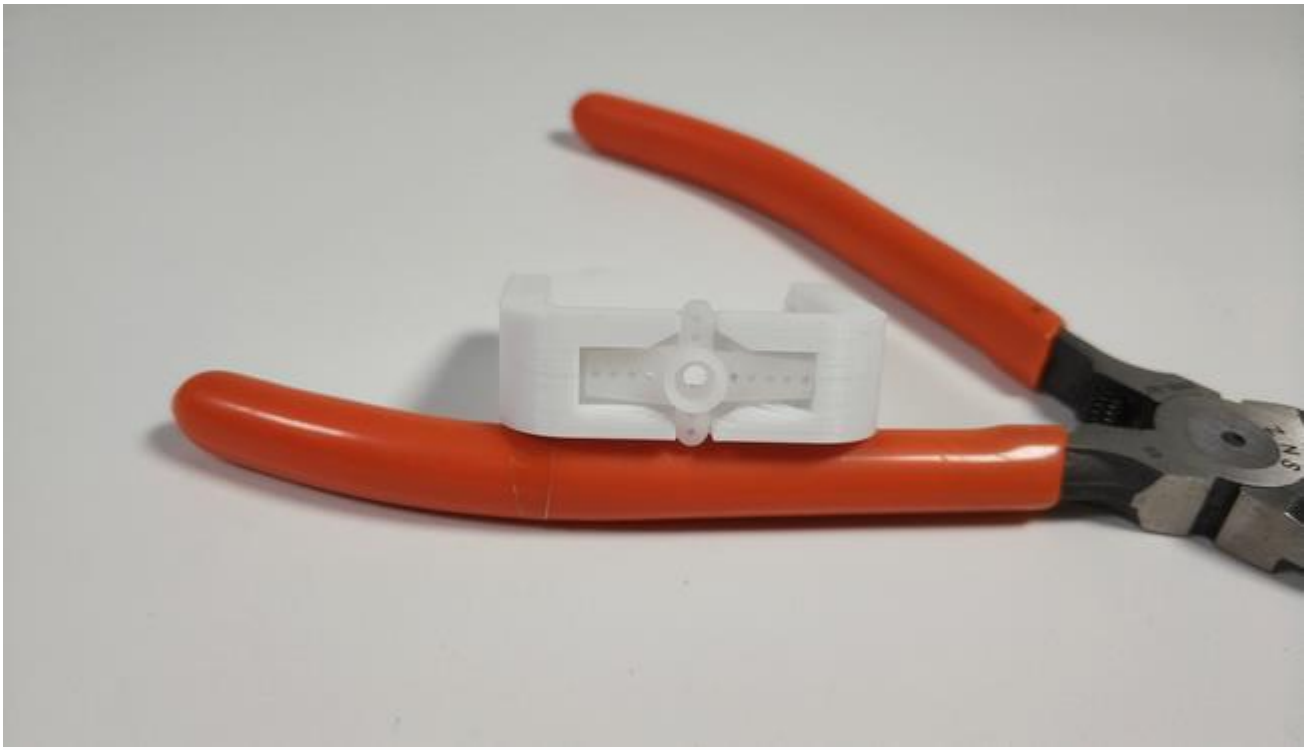
Combination process

The first point to write first is that each servo should be installed with an initial position of 90°.

1.Screws

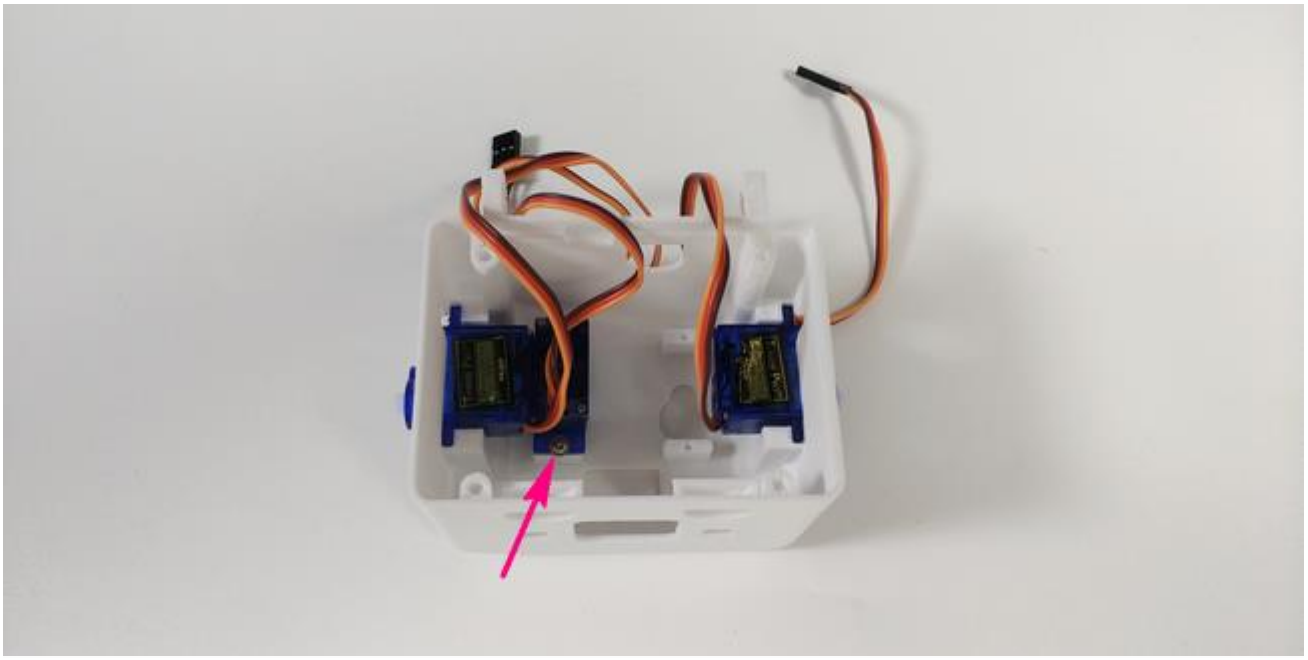


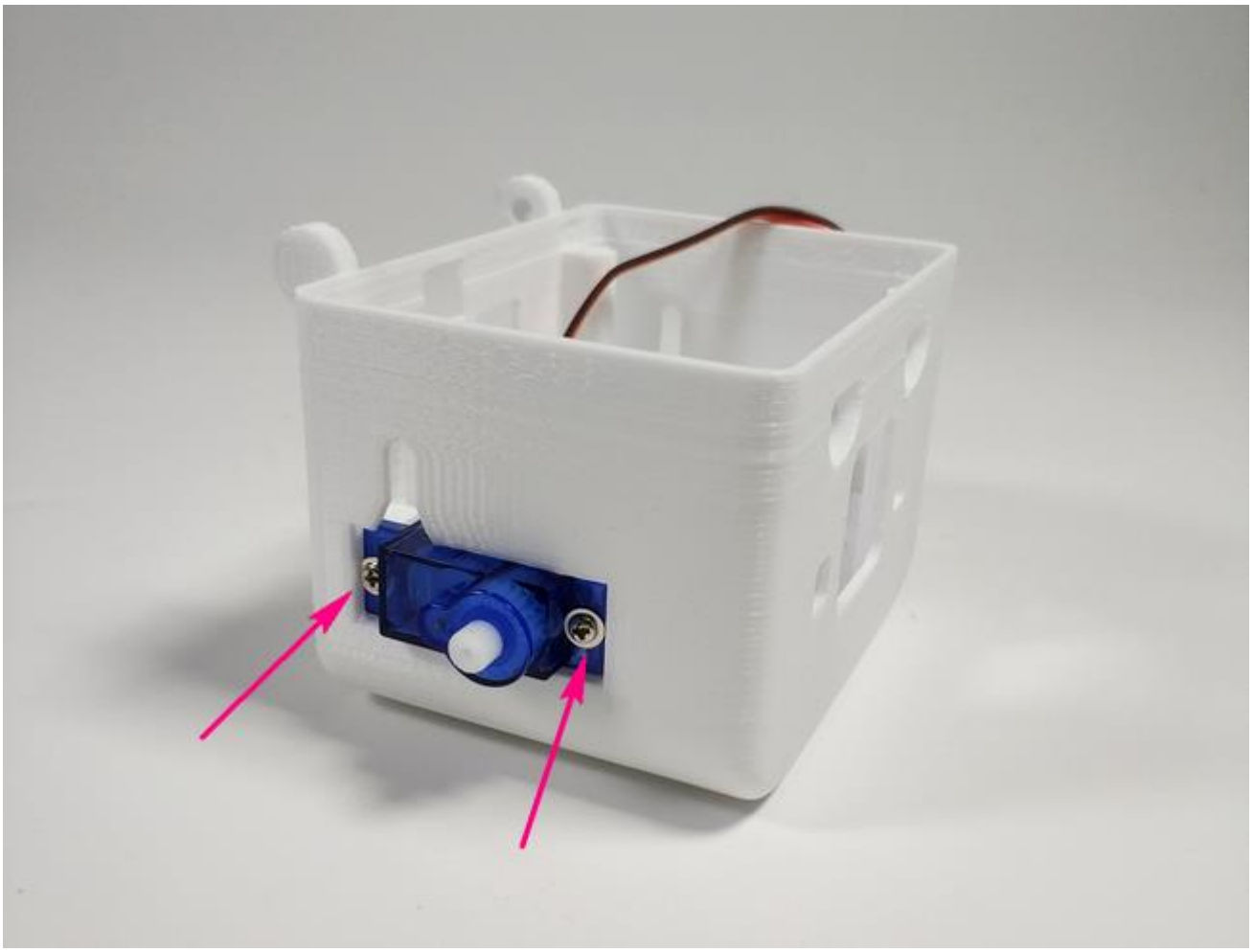
2. Take out the parts in the steering gear bag. As shown:



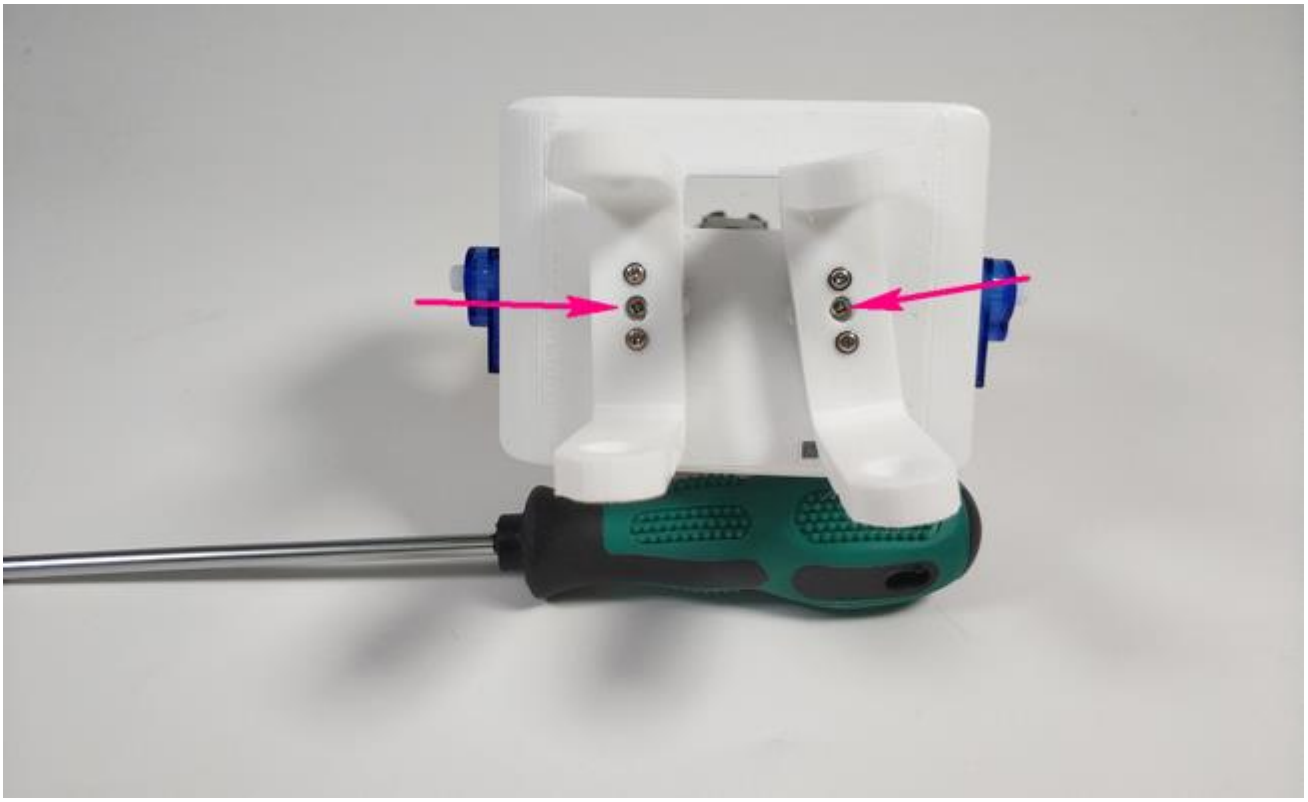
3.We respectively screwed them M1.2 screws and fixed them.

4.Fix 4 steering gears as 4 main joints in the shell. Note that each servo is fixed with M2.3 screws.

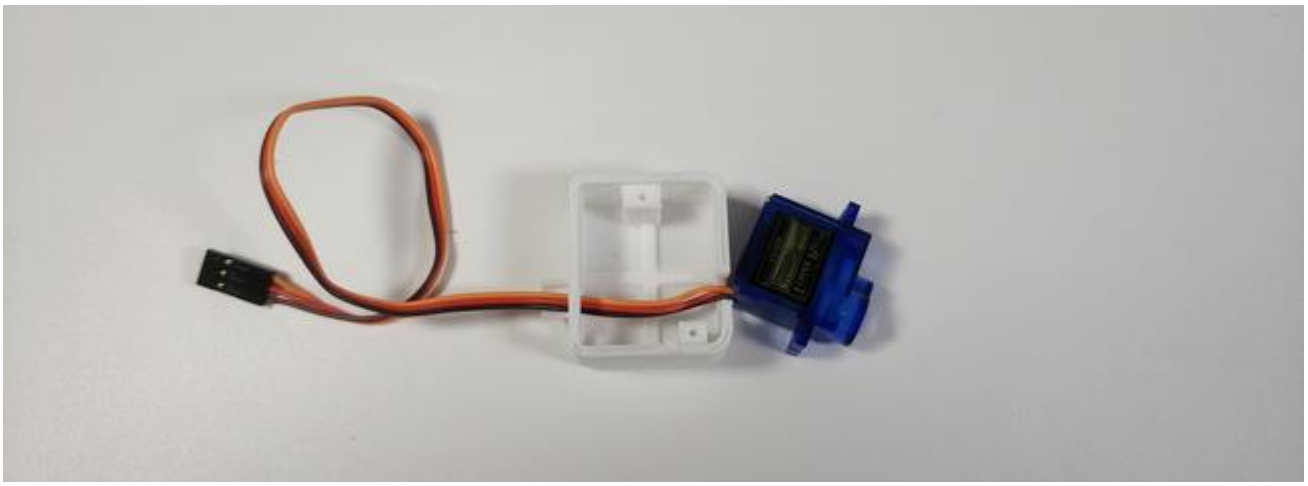




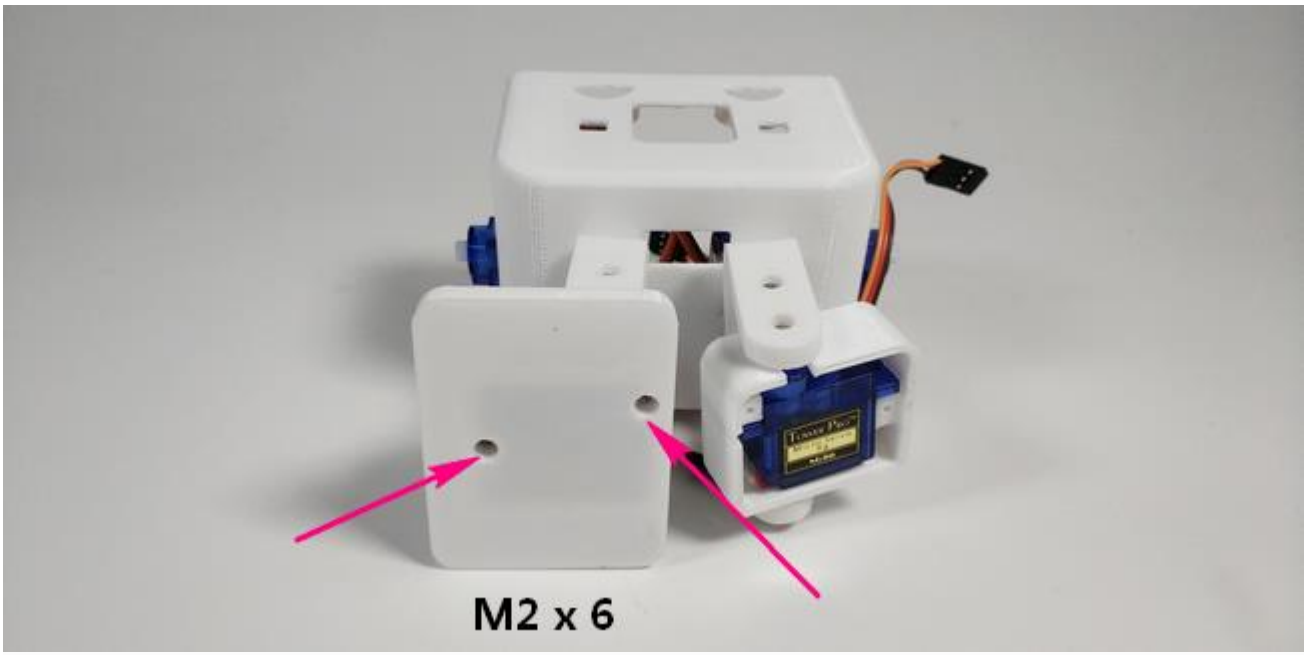
5.Each steering gear and support joint are fixed by M2 x 4 screws

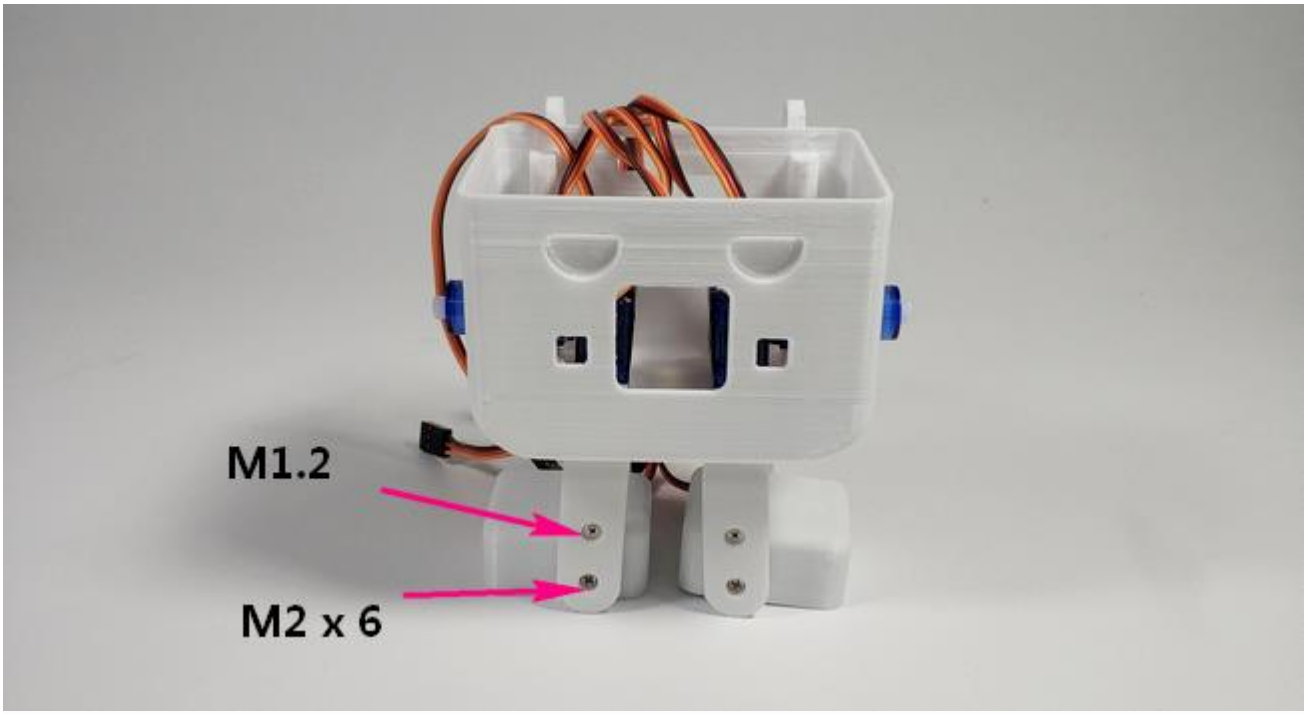


6.The part of the sole of the foot is installed as shown in the figure.

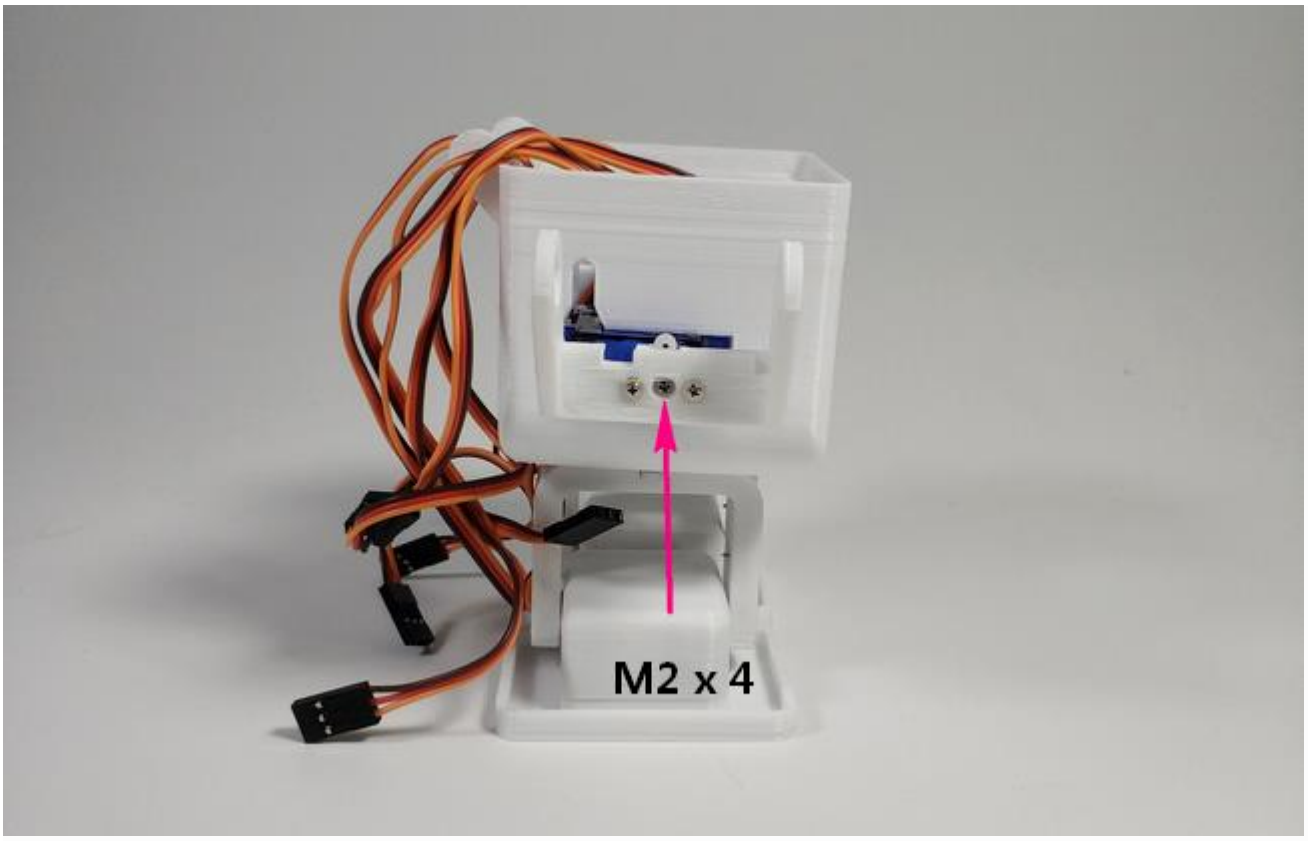


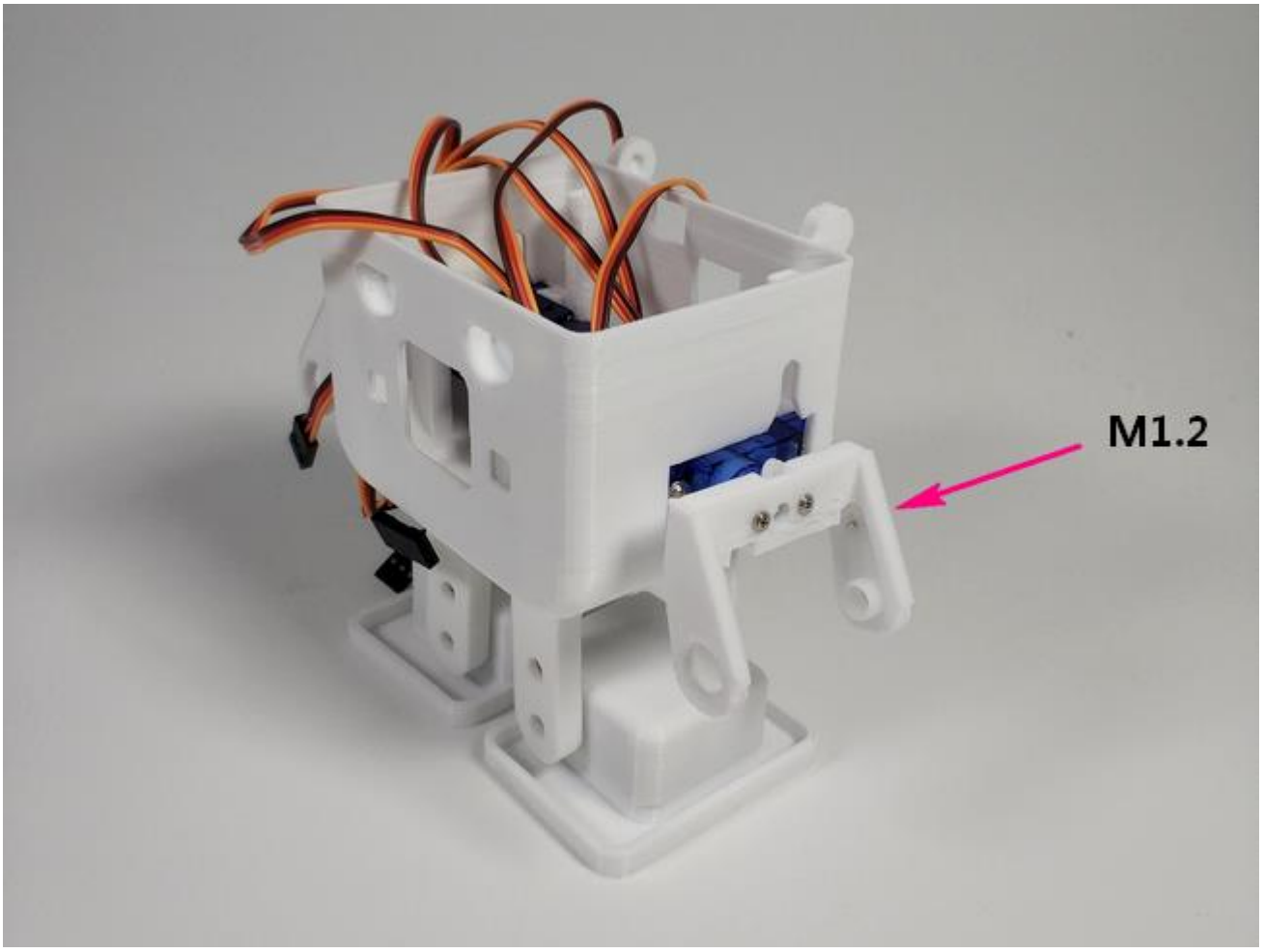
7.The connection between the sole and the leg and the screw selection are shown in the figure.





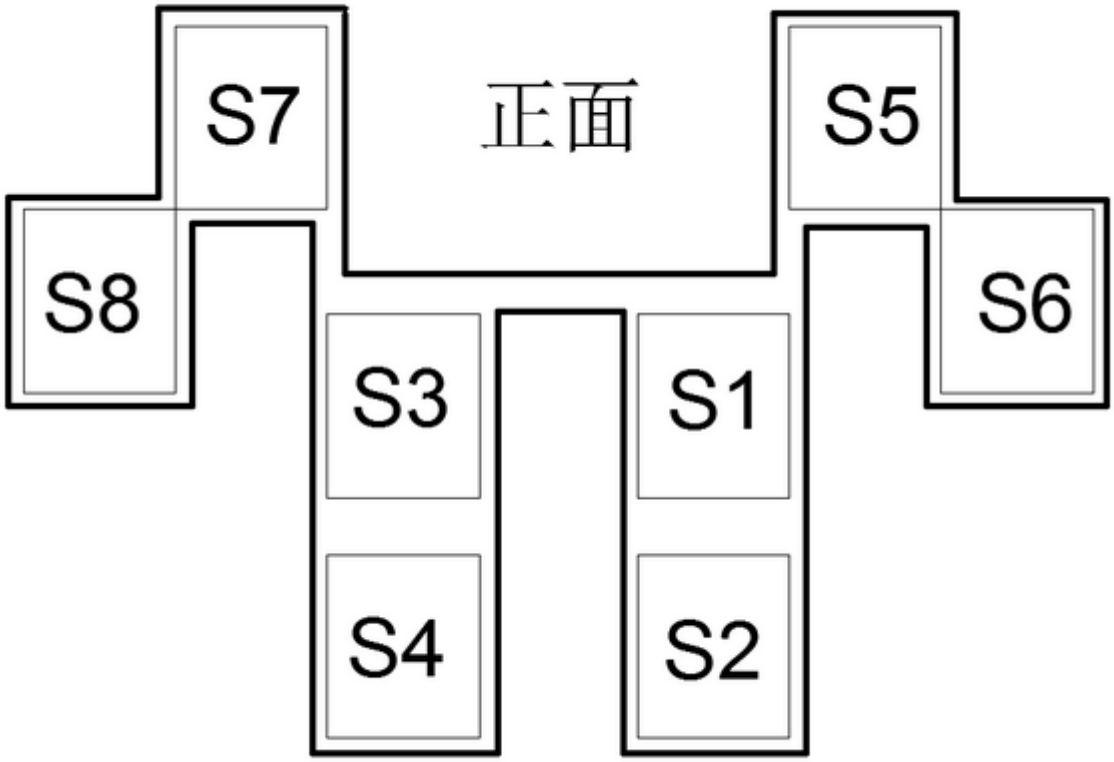
8.The arm part is fixed as shown in the figure. The M1.2 and the side area fixed joint steering gear are also used in the rear fixed steering gear.





9.The fixing of the hand is similar to that of the foot. Finally, the card is directly stuck in the work and becomes a job~

10.When everything is ready, follow the instructions in the figure.



Using environment

Programming mode：Kittenblock(base onScratch3.0)/MakecodeConnectable hardware：Microbit

Program installation reference

The first step in programming with makecode: Import the installation file

- What is needed to control the otto

- Through the operation of 8 steering gears of S1-S8 in different angles and sequences, the various OTTO movements are finally realized.

(For different steering gear installation error angles, the movement will be slightly biased, you can adjust the values in the array in the program by yourself)