

## **Annotation**

The purpose of this study is to develop a prototype tactile sensory platform for the study of anthropomorphic manipulations. I am exploring this issue by manufacturing and simply controlling a 2-DOF flat robotic finger, inspired by anatomical sequence, self-sufficiency and adaptability. To this end, I propose and implement a control structure for sensorimotor coordination, similar to the capture and fixation reflexes. This thesis describes in detail the mechanisms used to achieve these sensory, executive, and control goals, as well as the design philosophy and the biological factors behind them. The results of behavioral experiments are also described. An Arduino Uno board with a simple tactile-modulated control circuit is used.