

Supporting Information

Magnetorheological fluid based infinitely-regulatable triboelectric tactile sensor

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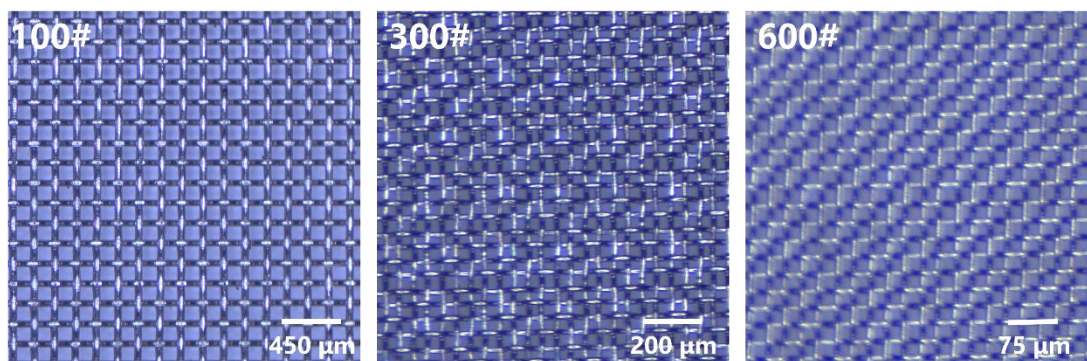


Figure S1. Optical images of the 100#, 300# and 600# wire meshes

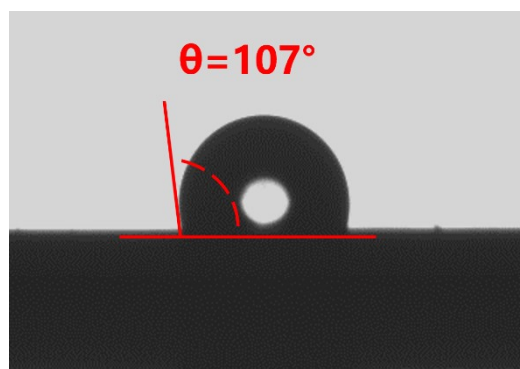


Figure S2. Water contact angle of raw silicone rubber.

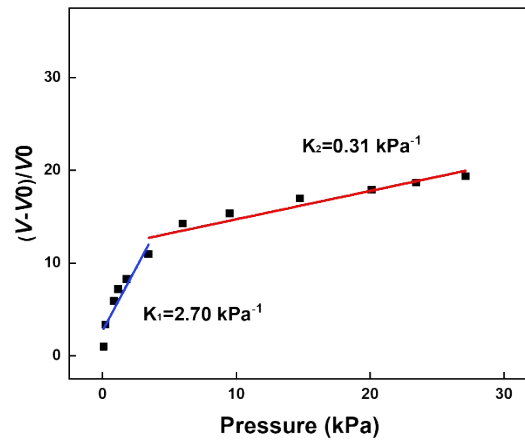


Figure S3. The relationship and linear fitting between the relative variations of voltage and pressure of MRF-TPS without microstructure.

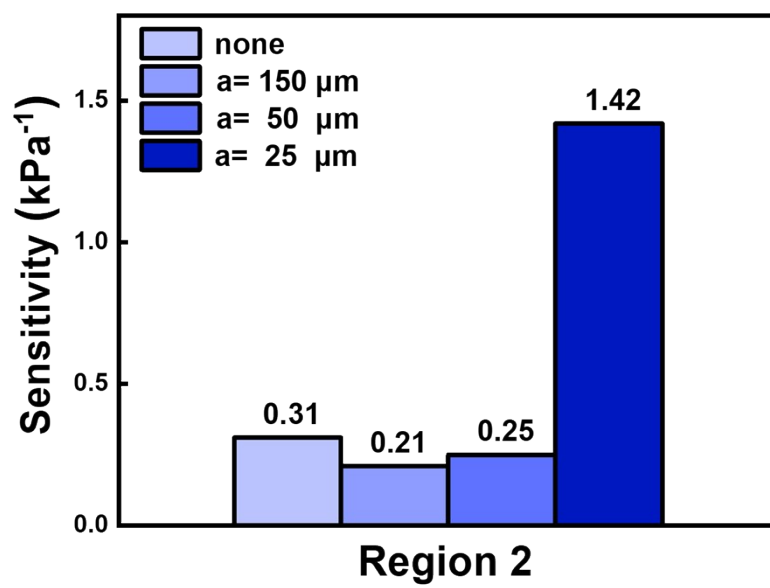


Figure S4. The summarized variation of sensitivity in high-pressure region of different MRF-TPSs.

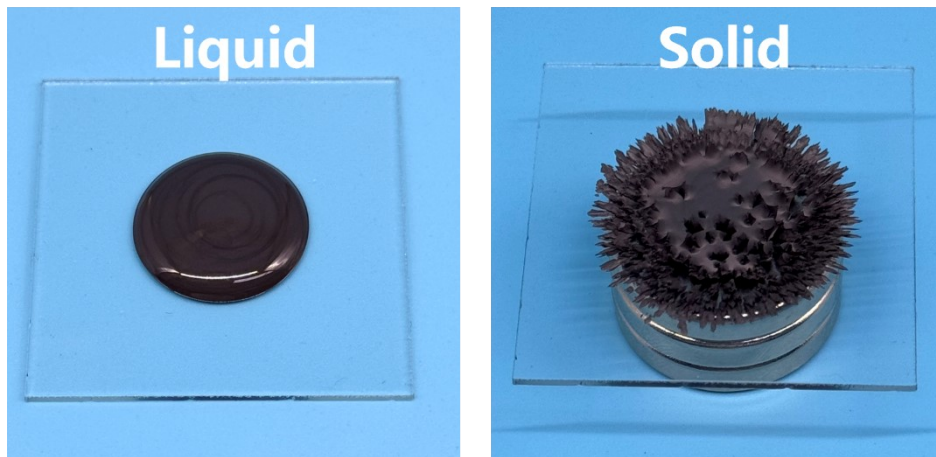


Figure S5. The optical images of magnetorheological fluid in different states.

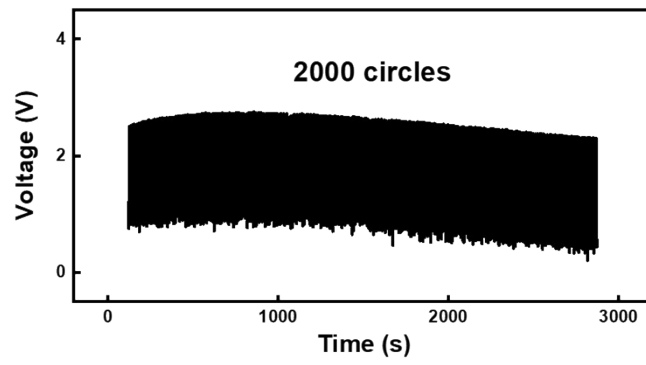


Figure S6. Periodic loading-unloading process of MRF-TPS in liquid-solid mode for 2000 cycles.

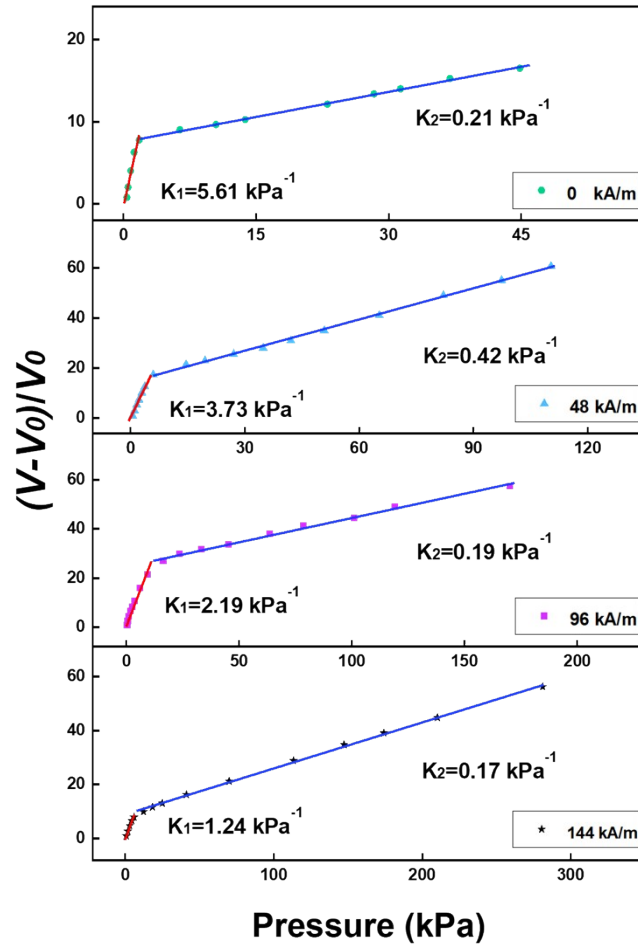


Figure S7. The relationship and linear fitting between the relative variations of voltage and pressure of 100#MRF-TPS under different magnet fields.

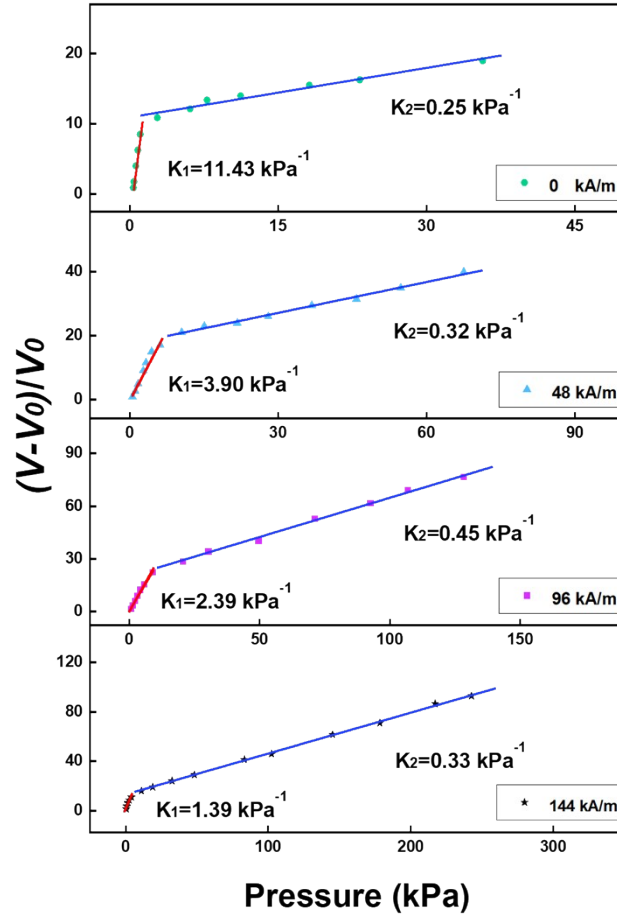


Figure S8. The relationship and linear fitting between the relative variations of voltage and pressure of 300#MRF-TPS under different magnet fields.

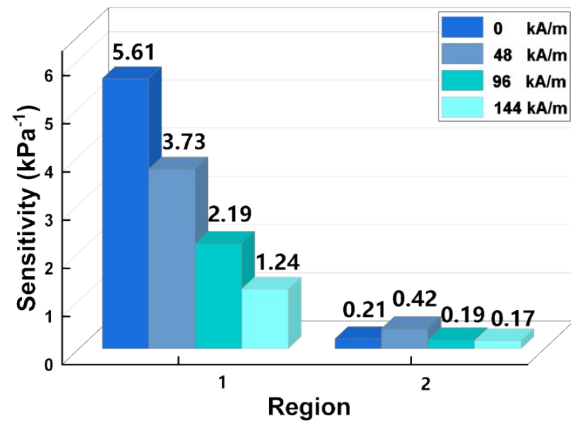


Figure S9. The summarized variation of sensitivity in two regions of 100#MRF-TPS under different magnet fields.

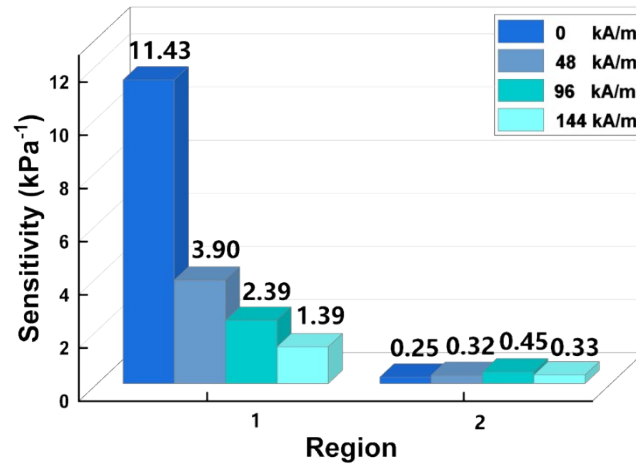


Figure S10. The summarized variation of sensitivity in two regions of 300#MRF-TPS under different magnet fields.