Supporting Information

Multimodal Fibrous Static and Dynamic Tactile Sensor

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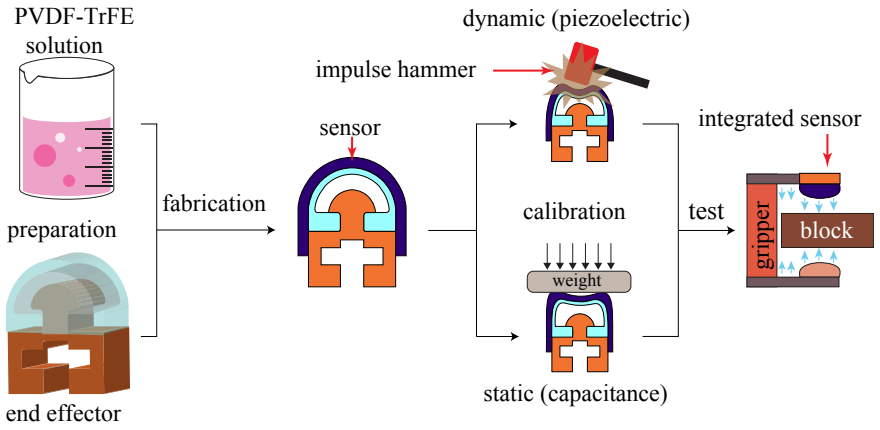

Figure S1: Flow of work, from (left) material and substrate preparation to (right) integrated sensor testing with robot.

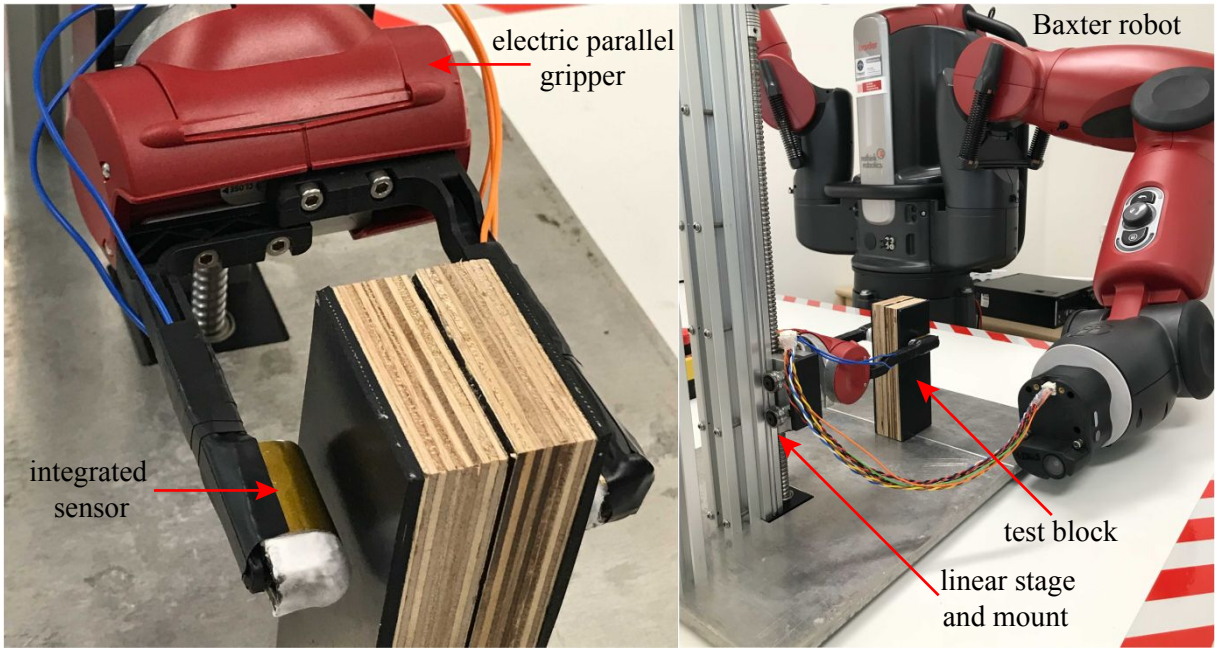

Figure S2: Experimental setup of the Baxter robot.

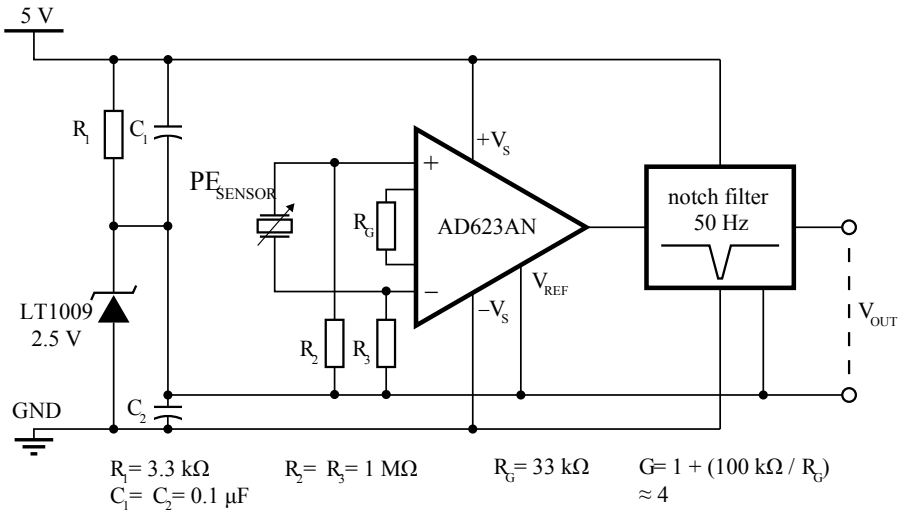

Figure S3: Diagram of circuit used in piezoelectric data acquisition. Notch filter removes some of the ambient noise from the power grid in Australia.

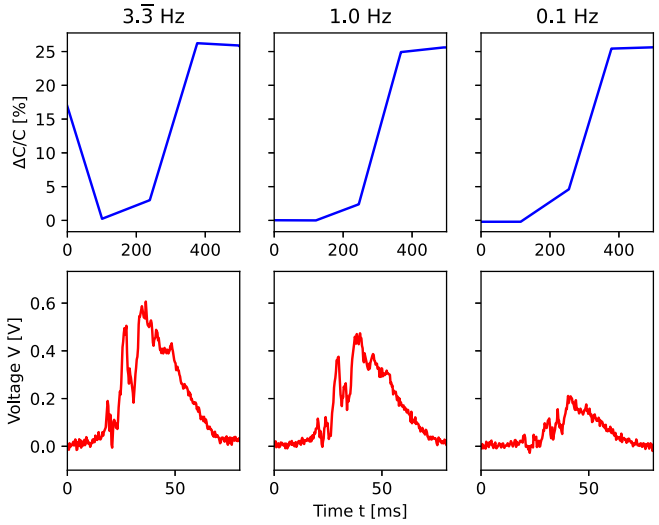

Figure S4: (top) capacitive and (bottom) piezoelectric grip event peaks at different gripping frequencies. Signal can be seen to change in magnitude at different gripping frequencies. Units are shared in the y-axis. Constant gripping pressure of $P \approx 52.5$ kPa.

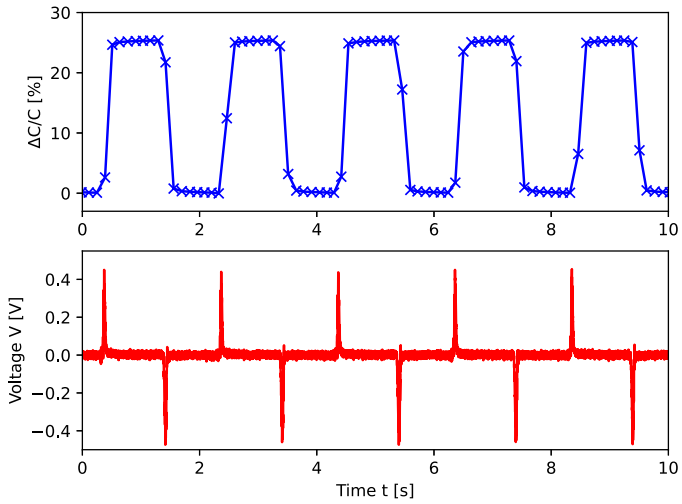

Figure S5: (top) capacitive and (bottom) piezoelectric effects, key data is aligned in the x-axis. Gripping rate and pressure is a constant, at $1.0\ Hz$ and ≈ 52.5 kPa, respectively.