Supporting Information

Magnetically Controlled Reversible Shape-morphing Microrobots with Real-time X-ray Imaging for Stomach Cancer Applications

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Supplementary Materials

Table S1. Design parameters of the EMA system.

Parameter	**Value**
Workspace diameter (mm)	40
Distance from end of the coil to the center of a workspace (mm)	60
Wire diameter (mm)	1.6
Number of turns	1368
Coil inner diameter (mm)	40
Coil outer diameter (mm)	77
Coil length (mm)	210
Core diameter (mm)	40
Core length (mm)	240
Resistance (Ω)	2.2

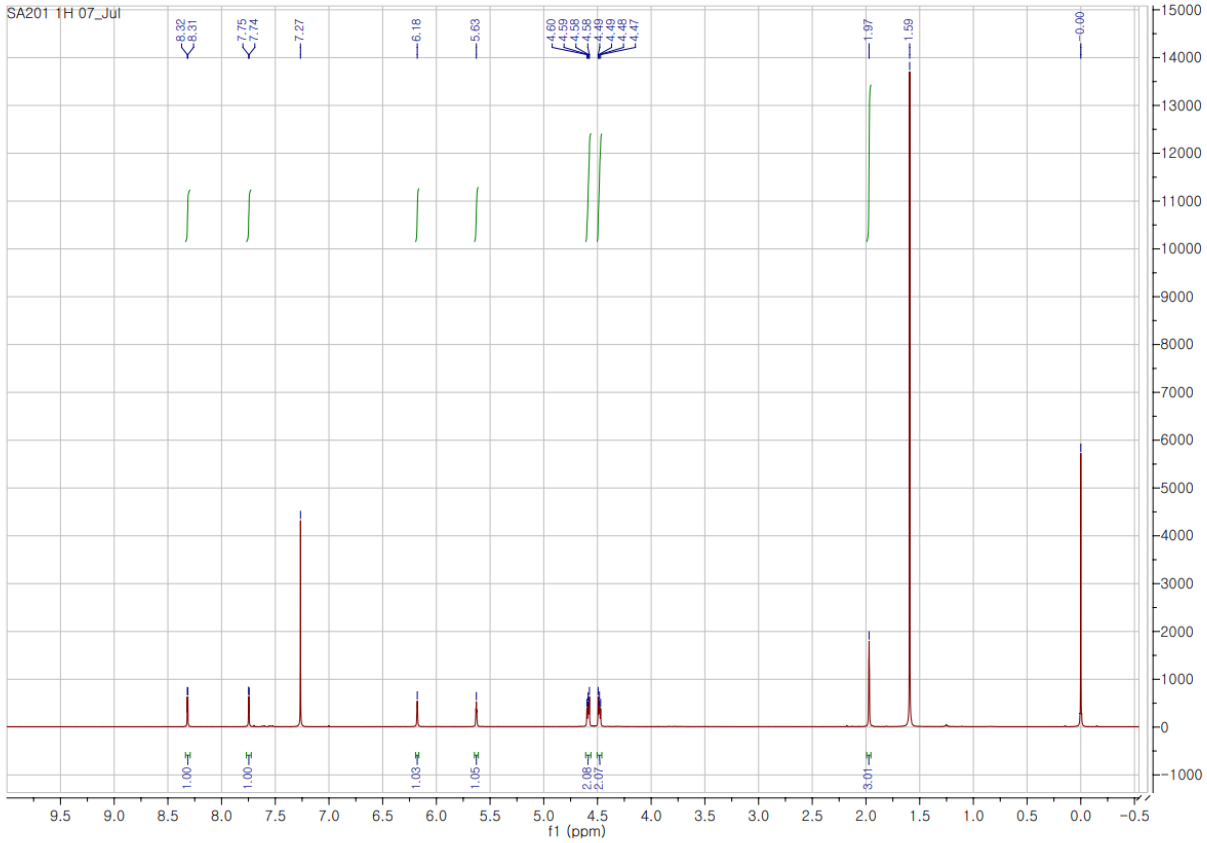

Fig. S1. ^{1}H NMR spectrum of mTIB.

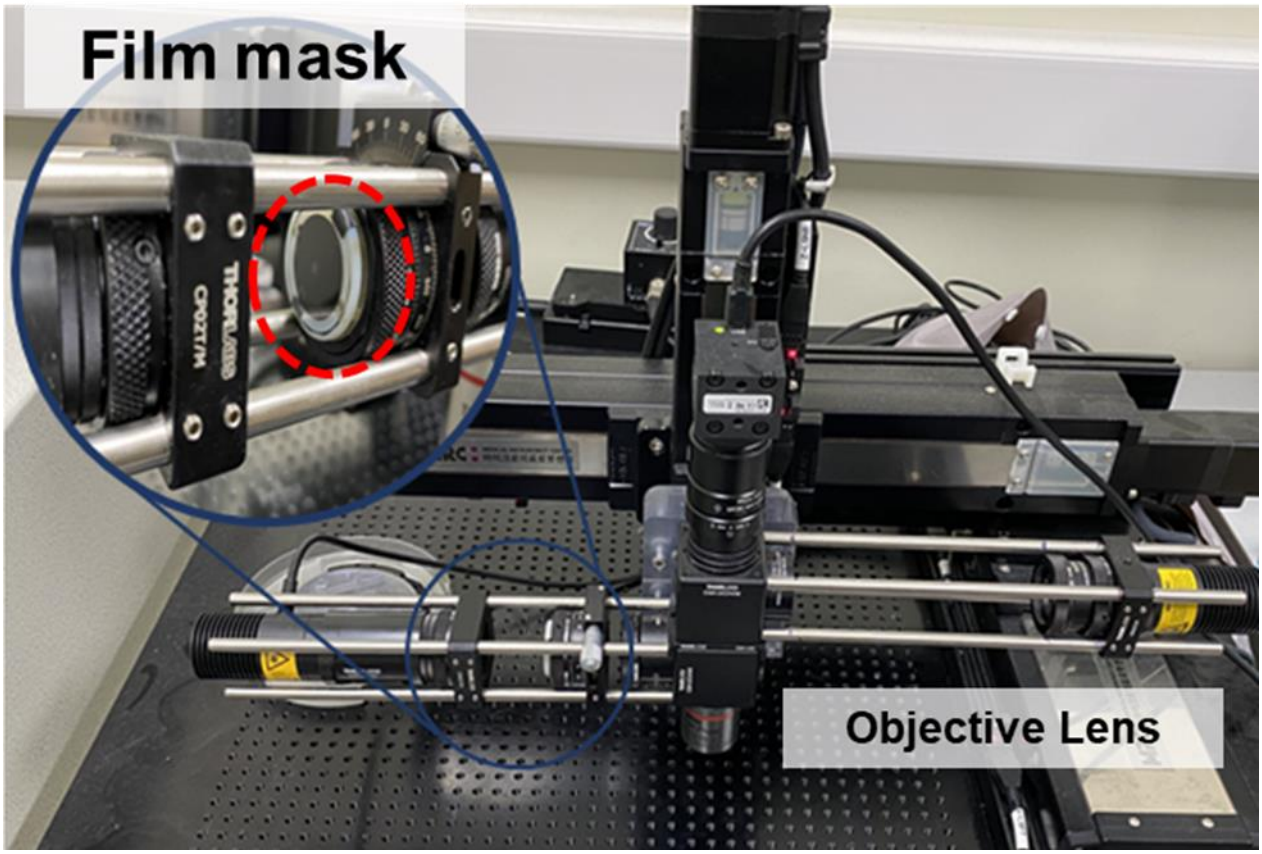

Fig. S2. The optical system used for microrobot fabrication.

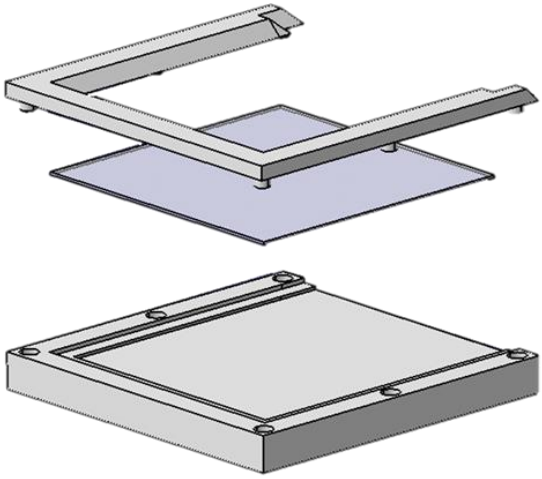

Fig. S3. Illustration of the chamber, which was fabricated using a three-dimensional printer

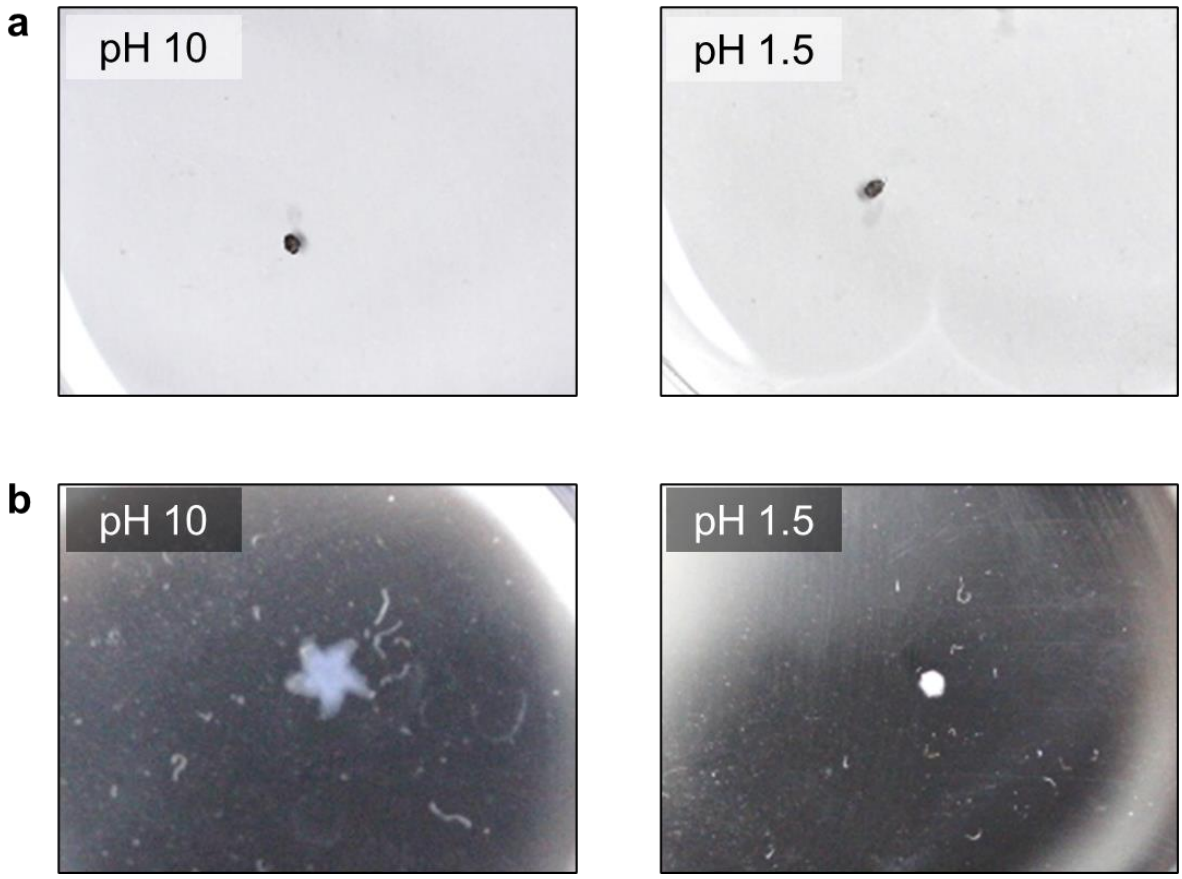

Fig. S4. Digital photographs of each material at different pH values (a) Composite resin (b) pHEMA.

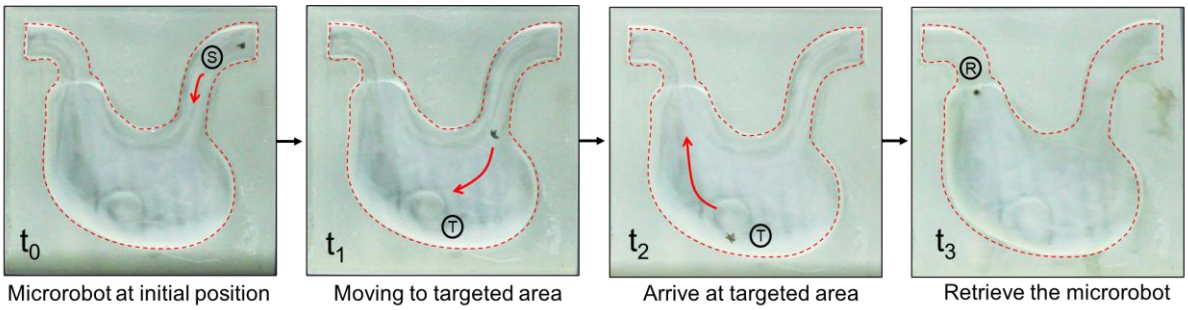

Fig. S5. Digital photographs of microrobot locomotion in a stomach-like channel.