Supplementary Material

Tactile Sensing and Control of Robotic Manipulator Integrating Fiber Bragg Grating Strain-Sensor

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**Supplementary Figure 1.** Cam-Hand finger before the integration of the soft polymer embedding the optical fiber. In the figure it is highlighted the groove for the insertion of the Dragon Skin 20 silicon.



Supplementary Figure . Experimental setup for assessing the performance of the sensorized finger.



Supplementary Figure . Experimental setup during the Dynamic Task