



## Supplementary materials for

Jiamiao MIAO, Xiaopu WANG, Yan ZHOU, Min YE, Hongyu ZHAO, Ruoyu XU, Huihuan QIAN, 2023. Magnetically driven microrobots moving in a flow: a review. *Front Inform Technol Electron Eng*, 24(11):1520-1540. <https://doi.org/10.1631/FITEE.2300054>

**Table S1 Detailed parameters of the flow system channels and the corresponding microrobots used, and the actuation and tracking methods**

System	Channel length	Channel size	Flow rate	Robot shape	Robot size	Actuation and tracking method
Lab flow system: Poiseuille	5.5 cm	100 $\mu\text{m}$ cylindrical channel	1.05 m/s	Sphere	10.82 $\mu\text{m}$ particles	MRI (Mathieu and Martel, 2006)
	2 cm	2.5 mm in width, 0.3 mm in height	12.2, 6.1 mm/s (in main and outlet branch)	Sphere	11 $\mu\text{m}$ in diameter	MRI (Mathieu and Martel, 2010)
	10 cm	1.6–4.8 mm in diameter	0–75 $\mu\text{L}/\text{min}$ (at an interval of 25 $\mu\text{L}/\text{min}$ )	Helical	$D_{\text{head}}=880 \mu\text{m}$ , wavelength=1 mm, $L_{\text{tail}}=4$ or 6 mm, $L_{\text{head}}, D_{\text{tail}}$ NM	Rotating magnetic field (Acemoglu and Yesilyurt, 2015)
	NM	150, 300 $\mu\text{m}$ in diameter	0.2 mm/s	Sphere	2.9 $\mu\text{m}$ (particle), 15, 40 $\mu\text{m}$ (cluster)	Rotating magnetic field (Ahmed et al., 2021)
Lab flow system: pulsatile	NM	7 mm in diameter	39–87 cm/s	Cylinder	1 mm in diameter, 10 mm in length	Electro-magnetic system (Choi et al., 2010b)
	NM	9.82 mm in diameter	$6 \times 10^{-6}$ , $7.1 \times 10^{-6} \text{ m}^3/\text{s}$	Sphere	1500 $\mu\text{m}$ in diameter	MRI (Tamaz et al., 2008)
	NM	3 mm in diameter	25 mm/s	Sphere	250 $\mu\text{m}$	Magnetic field gradient (Arcese et al., 2011)
Artificial blood system	12 mm	75 $\mu\text{m}$ in height, 3 mm in width	5–20 $\mu\text{L}/\text{min}$ for PBS, 1.12–12.26 mL/min for whole blood	Sphere	3, 7.8 $\mu\text{m}$ in diameter	Rotating magnetic field (Alapan et al., 2020)
	1 mm	0.1 mm in thickness, 4 mm in width	0.167 mm/s	Sperm like (cap diameter + sperm length > 60 $\mu\text{m}$ )	13 $\mu\text{m}$ (diameter of the cap)	Permanent magnetic field (Xu et al., 2020)
Ex vivo system	NM	2.6 mm in diameter	30 mm/s	Sphere	NM	Cylinder permanent magnet (Wang et al., 2021)
In vivo system	NM	NM	NM	Helical	8, 16 $\mu\text{m}$ in length	Rotating magnetic field (Servant et al., 2015)
	NM	NM	NM	Porous sphere	70, 90 $\mu\text{m}$ in diameter	Magnetic field gradient (Li et al., 2018)
	NM	Diameter of carotid artery of a living swine	Flow rate of carotid artery of a living swine	Sphere	1.5 mm in diameter	Magnetic field gradient (Martel et al., 2007)
	NM	10–15 mm in diameter	50–60 heart beats/min	Cylinder	1 mm in diameter, 10 mm in length	Uniform magnetic field and magnetic field gradient (Choi et al., 2010a)
	5 mm	0.2 mm in width	100, 400, 700 $\mu\text{m}/\text{s}$	NM	NM	Rotating magnetic field (Zhang et al., 2021)

NM: not mentioned

## References

- Acemoglu A, Yesilyurt S, 2015. Effects of Poiseuille flows on swimming of magnetic helical robots in circular channels. *Microfl Nanofl*, 19(5):1109-1122. <https://doi.org/10.1007/s10404-015-1629-6>
- Ahmed D, Sukhov A, Hauri D, et al., 2021. Bioinspired acousto-magnetic microswarm robots with upstream motility. *Nat Mach Intell*, 3(2):116-124. <https://doi.org/10.1038/s42256-020-00275-x>
- Alapan Y, Bozuyuk U, Erkok P, et al., 2020. Multifunctional surface microrollers for targeted cargo delivery in physiological blood flow. *Sci Robot*, 5(42):eaba5726. <https://doi.org/10.1126/scirobotics.aba5726>
- Arcese L, Fruchard M, Ferreira A, 2011. Endovascular magnetically guided robots: navigation modeling and optimization. *IEEE Trans Biomed Eng*, 59(4):977-987. <https://doi.org/10.1109/TBME.2011.2181508>
- Choi J, Jeong S, Cha K, et al., 2010a. Position stabilization of microrobot using pressure signal in pulsating flow of blood vessel. *SENSORS*, p.723-726. <https://doi.org/10.1109/ICSENS.2010.5690046>
- Choi J, Jeong S, Cha K, et al., 2010b. Positioning of microrobot in a pulsating flow using EMA system. Proc 3<sup>rd</sup> IEEE RAS & EMBS Int Conf on Biomedical Robotics and Biomechanics, p.588-593. <https://doi.org/10.1109/BIOROB.2010.5628036>
- Li J, Li X, Luo T, et al., 2018. Development of a magnetic microrobot for carrying and delivering targeted cells. *Sci Robot*, 3(19):eaat8829. <https://doi.org/10.1126/scirobotics.aat8829>
- Martel S, Mathieu JB, Felfoul O, et al., 2007. Automatic navigation of an untethered device in the artery of a living animal using a conventional clinical magnetic resonance imaging system. *Appl Phys Lett*, 90(11):114105. <https://doi.org/10.1063/1.2713229>
- Mathieu JB, Martel S, 2006. Magnetic steering of iron oxide microparticles using propulsion gradient coils in MRI. Int Conf of the IEEE Engineering in Medicine and Biology Society, p.472-475. <https://doi.org/10.1109/IEMBS.2006.259818>
- Mathieu JB, Martel S, 2010. Steering of aggregating magnetic microparticles using propulsion gradients coils in an MRI scanner. *Magn Reson Med*, 63(5):1336-1345. <https://doi.org/10.1002/mrm.22279>
- Servant A, Qiu F, Mazza M, et al., 2015. Controlled in vivo swimming of a swarm of bacteria-like microrobotic flagella. *Adv Mater*, 27(19):2981-2988. <https://doi.org/10.1002/adma.201404444>
- Tamaz S, Gourdeau R, Chanu A, et al., 2008. Real-time MRI-based control of a ferromagnetic core for endovascular navigation. *IEEE Trans Biomed Eng*, 55(7):1854-1863. <https://doi.org/10.1109/TBME.2008.919720>
- Wang QQ, Chan KF, Schweizer K, et al., 2021. Ultrasound Doppler-guided real-time navigation of a magnetic microswarm for active endovascular delivery. *Sci Adv*, 7(9):eabe5914. <https://doi.org/10.1126/sciadv.abe5914>
- Xu H, Medina-Sánchez M, Maitz MF, et al., 2020. Sperm micromotors for cargo delivery through flowing blood. *ACS Nano*, 14(3):2982-2993. <https://doi.org/10.1021/acsnano.9b07851>
- Zhang H, Li Z, Gao C, et al., 2021. Dual-responsive biohybrid neutroblots for active target delivery. *Sci Robot*, 6(52):eaaz9519. <https://doi.org/10.1126/scirobotics.aaz9519>