

## FACTS

Technical data	NPS-150P	NPS-300 P	NPS-400 P	NPS-400 PD
Stroke, cube (mm)	15	28	60	105
Range Pitch, Yaw,Roll (°)	+/- 20	+/- 18	+/- 20	+/- 20
Stroke Z (mm)	20	55	105	175
Force (N)	48	192	384	768
Velocity (mm/sec)	200	200	200	200

Encoder resolution ( $\mu m$ )	0.05	0.05	0.05	0.05
Repeatability (µm)	< 0.5	< 0.5	< 0.5	< 0.5
Stage Base (D/mm)	204	330	475	762

## DESCRIPTION

MICOS presents NEW NanoPod NPS-series (parallel kinematic robotic) promise to revolutionize the manufacturing processes of products requiring nanometer resolution and repeatability. With 5 nanometer resolution around a virtual point in space ( Pivot point ) coupled with speeds of up to 110mm/sec these Hexapods form the basis of the next generation of automated nano-positioning systems for the most demanding applications in photonics, packaging, test, micro machining, defense systems, measurement, medical and semiconductor manufacturing. The inherent nature of the design means that settling times after a move are less than 2ms with no servo dither. In addition, the frictional force between the linear motor and the motion linkage means no hysteresis or loss of position if the power is lost. Hexapods with additional preparation can meet class 10 clean room standards. MICOS can also provide systems that will work in vacuum chambers 10 to the minus 10 Torr. Plus the robotic systems have no electromagnetic generation. To asuure performance of complex forward and inverse kinematic equations in a parallel structure the controller system is critical therefore MICOS has chosen Delta Tau.

The UMAC (Universal Motion and Automation Controller ) is a modular PMAC systembuilt with a set of 3U- format Eurocards. The configuration of any UMAC system starts with the selection of the Turbo PMAC CPU and continues with the addition of the necessary axes boards, I/O boards, communication interfaces (USB, Ethernet, etc.) and 4096 encoder interpolators. The Turbo PMAC motion controller inside the UMAC system provides the necessary structure to enable the user to easily implement and execute complex kinematic calculations. Kinematic calculations are required when there is an mathematical non-linear relationship between the tool-tip coordinates and the matching positions of the actuator ( joints )of the mechanism, typical in non-cartesian geometries. This capability permits the motion for the machine to be programmed in the natural coordinates of the tool-tip, usually cartesian coordinate, whatever the underlying geometry of the machine. The " forward-kineamtic" calculations use the joint positions as input, and convert them to tooltip coordinates.

## NanoPod System





NPS-350 P	5952-9-3110
NPS-350 P 10-3 mbar	5952-9-3117
NPS-350 P 10-7 mbar	5952-9-3118
NPS-350 P 10-10 mbar	5952-9-3119
NPS-400 P	5953-9-6110
NPS-400 P 10-3 mbar	5953-9-6117
NPS-400 P 10-7 mbar	5953-9-6118
NPS-400 P 10-10 mbar	5953-9-6119
NPS-400 PD	5954-9-7110
NPS-400 PD 10-3 mbar	5954-9-7117
NPS-400 PD 10-7 mbar	5954-9-7118
NPS-400 PD 10-10 mbar	5954-9-7119

An one-day introductory training at MICOS is included in the price.

Founded in 1990, MICOS specializes in the development, manufacturing and marketing of ultra-high precision positioning components and systems for research and industry. We are experts in vacuum, ultra-high vacuum, clean room, and extreme climate environments down to 77 Kelvin.

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