Table of Contents

Foreword xvii

Introduction xxi

Chapter 1. The Physics of the Microworld 1
Michaël GAUTHIER, Pierre LAMBERT and Stéphane RÉGNIER

1.1. Introduction 1
1.1.1. Scale effect 1
1.1.2. Illustration of the scale effect 2
1.1.3. Microworlds 3
1.2. Details of the microworld 4
1.2.1. Perception 5
1.2.1.1. Position-sensing 5
1.2.1.2. Force-sensing 6
1.2.2. Design of microactuators and fabrication technology 7
1.2.3. Micro-object behavior 7
1.2.4. Environmental control 8
1.2.5. Repeatability and dexterity of microrobots 8
1.2.6. Summary 8
1.3. Surface forces 8
1.3.1. Van der Waals forces 9
1.3.1.1. Origins 10
1.3.1.2. Intermolecular van der Waals potential 11
1.3.1.3. Integration of the intermolecular potential 12
1.3.1.4. Hamaker constant 14
1.3.1.5. Lifshitz theory 14
1.3.1.6. Combination equations 16
1.3.1.7. Retardation effects in van der Waals forces 16

1.3.1.8. Simplified Derjaguin model 17
1.3.1.9. Numerical approach 19
1.3.2. Surface tension effects: capillary forces 22
1.3.3. Electrostatic forces 35
1.3.3.1. Plane-plane and plane-sphere models 36
1.3.3.2. Conical model 38
1.3.3.3. Asymptotic model 38
1.3.3.4. Inclined conical model 39
1.3.3.5. Hyperboloid model 40
1.4. Contact forces 40
1.4.1. Introduction to the thermodynamics of surfaces 40
1.4.2. Various models 42
1.4.2.1. Hertz model 42
1.4.2.2. JKR model 44
1.4.2.3. DMT model 45
1.4.2.4. Dugdale model 45
1.4.3. Transition between surface energy and the Hamaker constant . . . 46
1.5. Experimental analysis of forces for micromanipulation 48
1.5.1. The atomic force microscope 48
1.5.1.1. Description of an atomic force microscope 48
1.5.1.2. Method of measurement 50
1.5.1.3. Pull-off forces and van der Waals forces 52
1.5.1.4. Electrostatic forces 54
1.5.2. Measurement of capillary forces 56
1.5.2.1. Description of the force measurement system 56
1.5.2.2. Analysis of the measurement of force-distance characteristics 57
1.6. Forces in liquid media 60
1.6.1. Impact of the liquid medium on surface forces and adhesive forces 60
1.6.1.1. Impact of the liquid medium on capillary forces 60
1.6.1.2. Impact of liquids on the electrostatic force 60
1.6.1.3. Impact of liquid on the pull-off force 61
1.6.1.4. Impact of liquid on van der Waals forces 61
1.6.1.5. Some measurements in water 62
1.6.2. Electric double-layer models 62
1.6.2.1. Surface charges in liquid media 63
1.6.2.2. Qualitative models of the electric double layer 64
1.6.2.3. Stern model 64
1.6.2.4. Zeta potential 65
1.6.2.5. Poisson-Boltzmann equation 66
1.6.3. Sphere-sphere and sphere-plane interactions 67
1.6.3.1. LSA method 67

1.6.3.2. Derjaguin method 68
1.6.3.3. Enhanced formulae 69
1.6.3.4. DLVO theory 71
1.6.3.5. XDLVO model 72
1.6.4. Impact of hydrodynamic effects on immersed manipulation 74
1.6.4.1. Fluid regime relevant to microrobotics 74
1.6.4.2. Flow laws 75
1.6.4.3. Applied forces 77
1.6.4.4. Impact on the behavior of micro-objects 77
1.7. Friction and roughness 78
1.7.1. Simplified description of microscopic friction 78
1.7.1.1. Admonton's laws 78
1.7.1.2. The Bowden and Tabor adhesion model 78
1.7.1.3. Single asperity approach 80
1.7.1.4. Microscopic approach 80
1.7.2. Roughness 80
1.7.2.1. Surface profiles: a multiscale problem 81
1.7.2.2. Surface profile measurement 82
1.7.2.3. Roughness models 82
1.7.2.4. Roughness models and fabrication processes 84
1.8. Relevant parameters and indicators 85
1.8.1. Relevant parameters 85
1.8.2. List of constants 86
1.8.2.1. Hamaker constants 86
1.8.2.2. Surface energy 87
1.8.2.3. Contact angle and surface tension 87
1.9. Exercises 88
1.9.1. Impact of viscous effects on the behavior of micro-objects 88
1.9.2. Illustration of the impact of capillary forces during micromanipulation in an immersed medium 89
1.9.3. Estimating the van der Waals force for an interaction between a cone and a plane using the Derjaguin method 90
1.9.4. Analysis of the experimental force curve 90
1.9.5. Numerical calculation of the capillary force between two parallel plates 91
1.9.6. Calculation of the capillary force by derivation of the interfacial energy 92
1.9.6.1. Useful information 92
1.9.6.2. Force between a sphere and a plane 93
1.9.7. Choice of probe for force measurement 94
1.10. List of symbols 95

Chapter 2. Actuators for Microrobotics 99
Nicolas CHAILLET, Moustapha HAFEZ and Pierre LAMBERT

2.1. Introduction 99
2.2. Principles of motion and guiding 100
2.2.1. Motion generation 100
2.2.2. From sliding guidance to compliant guidance 104
2.3. Classification of actuators 111
2.4. Piezoelectric actuators 113
2.4.1. Introduction to piezoelectricity 113
2.4.2. Principles of piezoelectric materials 115
2.4.3. Ferroelectricity in piezoelectric ceramics 116
2.4.4. Properties of piezoelectric ceramics 117
2.4.4.1. Mechanical deformations 117
2.4.4.2. Electrical displacement 117
2.4.4.3. Generalization to 3D space 118
2.4.5. Multilayer (stack) actuators 121
2.4.6. Bimorph (bender) actuators 122
2.4.7. Stick-slip actuators 125
2.5. Electrostatic actuators 126
2.5.1. Principles 129
2.5.2. Elementary electrostatic actuator 130
2.5.2.1. Vertical actuator with parallel plates 130
2.5.2.2. Lateral actuator using parallel plates 133
2.5.2.3. Scale effect 135
2.5.3. Comb drive 137
2.5.4. Scratch-drive actuator 138
2.5.5. Conclusion 141
2.6. Thermal actuators 141
2.6.1. Scale effect 141
2.6.2. Actuators based on thermal expansion 143
2.6.2.1. Thermal bilayer 144
2.6.2.2. Thermal gradient microactuators 148
2.6.3. Shape memory alloys 151
2.6.3.1. Preamble 151
2.6.3.2. Principle 151
2.6.3.3. One-way memory effect 155
2.6.3.4. Two-way memory effect 155
2.6.3.5. Applications in micromanipulation 156
2.6.3.6. Other materials 159
2.7. Electro-active polymers 160
2.7.1. Ionic polymers 160
2.7.1.1. IPMC polymers (*ionic polymer metal composites*) 160
2.7.1.2. Conductive polymers 161

2.7.2. Electrical polymers 163
2.7.2.1. Dielectric elastomers 163
2.7.2.2. Piezoelectric polymers 165
2.8. Magneto-/electrorheological fluids 165
2.8.1. Physics of MR fluids 166
2.8.2. Example of fluid application: haptic interface for musical keyboards 168
2.9. Summary 170
2.10. Suppliers of active materials 170
2.10.1. Suppliers of piezoelectric materials 170
2.10.2. Suppliers of shape memory alloys 173
2.10.3. Suppliers of electro-active polymers 173
2.10.4. Supplier of MR fluids 173
2.10.5. Supplier of magnetostrictive actuators 173
2.11. Exercises 173
2.11.1. Dimensioning of a four-neck table 173
2.11.2. Case study of a multilayer actuator 174
2.11.3. Case study of a bimorph actuator 175
2.11.4. Motion of a dielectric 175
2.11.5. "xy" actuator 176
2.11.6. Analysis of a thermal bilayer actuator 178
2.11.7. Calculation for a simple AMF actuator 178

Chapter 3. Microhandling and Micromanipulation Strategies 179
Michaël GAUTHIER, Pierre LAMBERT and Stéphane RÉGNIER

3.1. Introduction 179
3.2. Contact-free micromanipulation and positioning 180
3.2.1. Using optical tweezers 180
3.2.2. Using electrostatic forces 183
3.2.2.1. Expression for the electrophoretic force 184
3.2.2.2. Dielectrophoretic torque 185
3.2.2.3. Application of dielectrophoresis in micromanipulation . . . 186
3.2.2.4. Particle positioning using electrophoresis 188
3.2.2.5. Use of a d.c. electric field 188
3.2.3. Using magnetic forces 189
3.2.4. Acoustic levitation 191
3.3. Contact-based micromanipulation and positioning 197
3.3.1. Using grippers with jaws 197
3.3.1.1. Monolithic actuator-based microgrippers 198
3.3.1.2. Multicomponent microgrippers 199
3.3.1.3. Gripper with passive jaws 201
3.3.2. Using phase changes 203
3.3.3. Vacuum gripping 206

3.3.4. Manipulation by adhesion 207
3.3.4.1. Description of a manipulation task 207
3.3.4.2. Discussion of the pick-up and release phases 208
3.3.4.3. Static pick-up and release experiments in dry media 211
3.3.5. Capillary gripping 212
3.4. Release strategies 220
3.4.1. Dynamic release 220
3.4.1.1. Bulk pick-up and selective release 224
3.4.2. Release of micro-objects through dielectrophoresis 226
3.4.3. Rolling 227
3.4.3.1. Experimental release using rolling 228
3.4.3.2. Precise release by rolling 229
3.5. Summary 230
3.6. Conclusion 234
3.7. Exercises 234
3.7.1. Acoustic levitation 234
3.7.2. Numerical study of inertial deposition 234
3.7.3. Numerical study of rolling 236
3.7.4. Establishing a frequency range for the validity of the simplified formula for the dielectrophoretic force 238
3.7.5. Determination of the Bode plot of the Clausius-Mosotti equation 239
3.7.6. Calculation of the dielectrophoretic force applied to a micro-object 239
3.7.7. Behavior of a laser-trapped object 241
3.7.8. Simultaneous manipulation of several micro-objects using a single laser 242

Chapter 4. Architecture of a Micromanipulation Station 243
Joël AGNUS, Mehdi BOUKALLEL, Cédric CLÉVY, Sounkalo DEMBÉLÉ and Stéphane RÉGNIER

4.1. Introduction 243
4.2. Kimenatics 244
4.2.1. Overview 244
4.2.2. Evolution and history 245
4.2.3. Range of available architectures 246
4.2.3.1. Mobile working post robots 247
4.2.3.2. Fixed working post robots 250
4.2.4. Current solutions 253
4.2.4.1. Commercial systems 253
4.2.4.2. Study and development of novel systems 254
4.2.4.3. Integration examples 256
4.2.4.4. Example: the μMAD system 257

4.3. Visual perception 261
4.3.1. Importance of the image 261
4.3.2. Imaging 262
4.3.3. Properties 263
4.3.4. Modeling and calibration 269
4.3.5. Improving the field of view 271
4.3.5.1. Physical solutions 271
4.3.5.2. Software-based solutions 272
4.3.6. Increasing the depth of field 276
4.3.7. High-resolution metrology 278
4.3.8. Reference control of the image capture system 279
4.3.8.1. A simple example: 2D visual servoing 281
4.4. Force sensing 283
4.4.1. Architecture of force measurement systems 285
4.4.1.1. Indirect measurement methods 286
4.4.1.2. Direct measurement methods 286
4.4.2. Force measurement using sensors integrated into a microprehensor 287
4.4.2.1. Examples of resistive strain gauges 287
4.4.2.2. Examples of capacitative force sensors 291
4.5. Introduction to sensor-based linear multivariable control 294
4.5.1. Microrobotic servo systems 294
4.5.2. Multivariable systems 295
4.5.2.1. Differential representation 295
4.5.2.2. Transfer matrix representation 296
4.5.2.3. State-space model 296
4.5.3. Concepts of controllability and observability 296
4.5.4. Controllability 297
4.5.5. Observability 297
4.5.6. Control techniques for multivariable systems 297
4.5.6.1. Control decoupling 297
4.5.6.2. Optimal linear quadratic control 299
4.6. Application to automation and remote operation for micromanipulation tasks 300
4.6.1. Force feedback control with one degree of freedom 300
4.6.2. Remote micromanipulation with one degree of freedom 304
4.6.2.1. Master device: “Brigit” haptic interface 304
4.6.2.2. Slave organ: μMAD micro-manipulator 305
4.6.2.3. Investigation of various couplings 306
4.6.2.4. Homothetic coupling 307
4.6.2.5. Passive coupling 308
4.6.2.6. Relative performance of the two coupling strategies 309
4.6.2.7. Industrial haptic interface 315

4.6.2.8. Control of the nanotranslator 316
4.6.2.9. Experimental results 317
4.7. Environmental control 318
4.7.1. Important environmental parameters 319
4.7.1.1. Temperature 319
4.7.1.2. Humidity level 320
4.7.1.3. Mechanical vibrations 321
4.7.1.4. Particles in suspension 321
4.7.1.5. Other relevant parameters 321
4.7.2. Consequences of changes in environmental parameters 322
4.7.3. Solutions to reduce the effects of environmental parameters 323
4.8. Applications 324
4.8.1. Artificial components 325
4.8.1.1. Industrial applications 325
4.8.1.2. Instrumentation and research 327
4.8.2. Manipulation for biological applications 331
4.8.2.1. Cell sorting and manipulation of individual cells 333
4.9. Conclusion 334
4.10. Exercises 334
4.10.1. Exercise 1 334
4.10.2. Exercise 2 334
4.10.3. Exercise 3 334

Chapter 5. Microtechnologies and Micromanipulation 335
Lionel BUCHAILLOT

5.1. Silicon surface machining processes 335
5.1.1. Introduction 335
5.1.2. Bulk machining of silicon 336
5.1.3. History of surface micromachining 339
5.1.4. Principle 340
5.1.5. Advantages and drawbacks 342
5.1.6. Organization of this chapter 342
5.2. Early demonstrators 343
5.2.1. Mobile micromechanisms 343
5.3. Standard processes and fabrication examples 346
5.3.1. The SUMMiT™ process 347
5.3.2. The MUMPs® process 348
5.4. Alternative surface machining processes 352
5.4.1. The HexSil process 353
5.4.2. The SCREAM process 355
5.5. Co-integration with electronics 356
5.5.1. Integrated fabrication process 357

5.5.2. Sequential construction: microelectronics followed by microstructures . . . 358
5.5.2.1. Sequential construction: microstructures followed by microelectronic circuits . . . 358
5.5.3. Microstructures formed during CMOS circuit post-fabrication . . 359
5.6. Consistency of surface micromachining . . . 360
5.6.1. Stiction . . . 361
5.6.1.1. Attraction due to capillary forces . . . 361
5.6.1.2. Adhesion through solid-solid contact forces . . . 362
5.6.1.3. Preventing stiction . . . 363
5.6.2. Fatigue in polycrystalline silicon . . . 366
5.6.2.1. Methodology and implementation of tests . . . 366
5.6.2.2. Damage and fatigue mechanisms . . . 366
5.7. Conclusion . . . 367

Chapter 6. Future Prospects . . . 369
Philippe LUTZ and Stéphane RÉGNIER

6.1. Micromachining . . . 369
6.1.1. The main characteristics of microfactories . . . 370
6.1.2. The main functions of a microfactory . . . 371
6.1.2.1. Micromanipulation and micropositioning . . . 372
6.1.2.2. Transport, positioning, supply and peripherals . . . 373
6.1.2.3. Perception . . . 375
6.1.2.4. Attachment . . . 375
6.1.3. Main implementations worldwide . . . 377
6.1.3.1. Multi-station microfactories . . . 379
6.1.3.2. Single-station microfactory . . . 382
6.1.3.3. Conclusion . . . 389
6.1.4. Proposed microfactory architecture . . . 389
6.1.4.1. Modular, reconfigurable and reorganizable micromanipulation stations . . . 392
6.2. Nanomanipulation . . . 395
6.2.1. Various microscopy techniques . . . 396
6.2.1.1. Transmission electron microscope . . . 396
6.2.1.2. Scanning electron microscope . . . 398
6.2.1.3. Comparison with optical microscopy . . . 398
6.2.1.4. Local probe microscopes . . . 399
6.2.2. Comparison of available imaging techniques . . . 400
6.2.3. Manipulation methods . . . 401
6.2.3.1. Electrophoresis . . . 401
6.2.3.2. Optical trap . . . 401
6.2.3.3. Local probe manipulation . . . 404
6.2.3.4. Comparison of methods . . . 406

6.2.3.5. Use of an AFM in a scanning electron microscope 406
6.2.3.6. Tele-nanomanipulation 409
6.2.4. The nanomanipulator 410
6.2.5. Telenanoproject 411
6.2.6. Zyvex, Texas 412
6.2.7. Conclusion 413

Chapter 7. Solutions to Exercises 415

7.1. Chapter 1 415
7.1.1. Impact of viscous effects on the behavior of micro-objects 415
7.1.2. Illustration of the impact of capillary forces during micromanipulation in an immersed medium 417
7.1.3. Estimating the van der Waals force for an interaction between a cone and a plane using the Derjaguin method 417
7.1.4. Analysis of the experimental force curve 419
7.1.5. Calculation of the capillary force by derivation of the interfacial energy 420
7.1.6. Numerical calculation of the capillary force between two parallel plates 421
7.1.7. Choice of cantilever for force measurement 423
7.2. Chapter 2 423
7.2.1. Dimensioning of a four-neck table 423
7.2.2. Study of the case of a multiayer actuator 424
7.2.3. Study of the case of a bimorph actuator 425
7.2.4. Motion of a dielectric 426
7.2.5. "xy" actuator 427
7.2.6. Calculation for a bilayer thermal actuator 428
7.2.7. Calculation for a simple SMA actuator 428
7.3. Chapter 3 429
7.3.1. Acoustic levitation 429
7.3.2. Numerical study of inertial deposition 429
7.3.3. Numerical investigation of rolling 432
7.3.3.1. Static model 432
7.3.3.2. Sliding condition 432
7.3.3.3. Calculating the parameters of the problem 432
7.3.3.4. Rolling condition 433
7.3.3.5. Rolling and sliding conditions 434
7.3.3.6. Simulation and analysis 434
7.3.3.7. Comments 434
7.3.4. Establishing a frequency range for the validity of the simplified formula for the dielectrophoretic force 436
7.3.5. Determination of the Bode plot for the Clausius-Mosotti equation 437

7.3.6. Calculation of the dielectrophoretic force applied to a micro-object 438
7.3.7. Behavior of a laser-trapped object 439
7.3.8. Simultaneous manipulation of several micro-objects using a single laser 441
7.4. Chapter 4 443
7.4.1. Exercise 1 443
7.4.2. Exercise 2 444
7.4.3. Exercise 3 445

Bibliography 447

List of Authors 481

Index 483