

Contents

| | | |
|----------|---|-----------|
| 1 | Techniques Developed for High-Speed AFM | 1 |
| | Toshio Ando | |
| 1.1 | Introduction | 1 |
| 1.2 | Imaging Speed and Feedback Bandwidth | 2 |
| 1.3 | Mechanical Devices in High-Speed AFM | 2 |
| 1.3.1 | Cantilevers | 2 |
| 1.3.2 | Scanners | 4 |
| 1.4 | Active Damping Techniques | 5 |
| 1.4.1 | Feedback Q -Control for z-Scanner | 5 |
| 1.4.2 | Feedforward Damping of x-Scanner | 6 |
| 1.4.3 | Practice of Active Damping of Scanner Vibrations | 7 |
| 1.5 | Dynamic PID Control | 8 |
| 1.6 | Drift Compensator | 9 |
| 1.7 | Bio-imaging | 10 |
| 1.7.1 | Dynamic Equilibrium at the Bacteriorhodopsin Crystal Edge | 10 |
| 1.7.2 | Structural Changes of Bacteriorhodopsin under Light | 12 |
| 1.8 | Conclusion | 13 |
| | References | 14 |
| 2 | High-Accuracy Atomic Force Microscope | 17 |
| | David L. Trumper, Robert J. Hocken, Darya Amin-Shahidi, Dean Ljubicic, Jerald Overcash | |
| 2.1 | Introduction | 18 |
| 2.2 | Mechanical Design | 19 |
| 2.2.1 | Overall Metrology System | 20 |
| 2.2.2 | AFM Head | 21 |

| | | |
|----------|---|-----------|
| 2.3 | Self-sensing Probe for Frequency Measuring AFM | 23 |
| 2.3.1 | Self-sensing AFM Probe | 23 |
| 2.3.2 | Electromechanical Model | 24 |
| 2.3.3 | Frequency Measuring AFM | 26 |
| 2.3.4 | Probe Electronics Implementation | 28 |
| 2.3.5 | Sensing Curves | 34 |
| 2.4 | Control and Instrumentation | 36 |
| 2.4.1 | System Overview | 36 |
| 2.4.2 | Period Estimation | 37 |
| 2.4.3 | Tracking Control | 37 |
| 2.5 | Experimental Results | 40 |
| 2.5.1 | Single-Point Tests | 40 |
| 2.5.2 | Imaging Tests at MIT | 41 |
| 2.5.3 | Imaging Test after <i>Integration with SAMM</i> | 43 |
| | References | 44 |
| 3 | High-Speed, Ultra-High-Precision Nanopositioning: A Signal Transformation Approach | 47 |
| | Ali Bazaei, Yuen K. Yong, S.O. Reza Moheimani, Abu Sebastian | |
| 3.1 | Introduction | 47 |
| 3.2 | Objectives | 49 |
| 3.3 | Signal Transformation | 49 |
| 3.4 | Investigation of System Robustness | 50 |
| 3.5 | Incorporating Robustness in Signal Transformation | 52 |
| 3.6 | Experimental Results | 53 |
| 3.6.1 | Tracking Performance and Noise | 54 |
| | References | 56 |
| | Appendix | 58 |
| 4 | 2DOF Control Design for Nanopositioning | 67 |
| | Chibum Lee, Gayathri Mohan, Srinivasa Salapaka | |
| 4.1 | Introduction | 67 |
| 4.2 | Two Degree-of-Freedom Design | 70 |
| 4.2.1 | Feedforward Control Design for Fixed Feedback System | 71 |
| 4.2.2 | Improving Robustness to Operating Conditions for Given Feedback System | 73 |
| 4.2.3 | Simultaneous Feedback and Feedforward Control Design | 75 |
| 4.2.4 | Role of Feedforward and Feedback Components | 78 |
| 4.3 | Summary | 79 |
| | References | 80 |

| | | |
|----------|---|-----|
| 5 | Improving the Imaging Speed of AFM with Modern Control Techniques | 83 |
| | Stefan Kuiper, Georg Schitter | |
| 5.1 | Introduction | 83 |
| 5.2 | Improved Control of the Lateral Scanning Motion | 85 |
| 5.2.1 | Iterative Learning Control | 86 |
| 5.2.2 | Self-sensing Piezo Actuation | 89 |
| 5.3 | Controlling the Tip-Sample Interaction Forces | 93 |
| 5.3.1 | Dual Actuation | 94 |
| 5.3.2 | Imaging Results | 97 |
| 5.4 | Conclusion | 97 |
| | References | 98 |
| 6 | Non-raster Scanning in Atomic Force Microscopy for High-Speed Imaging of Biopolymers | 101 |
| | Peter I. Chang, Sean B. Andersson | |
| 6.1 | Introduction | 101 |
| 6.2 | Overview of Local Raster Scanning | 102 |
| 6.2.1 | AFM System Block | 102 |
| 6.2.2 | Detector Block | 103 |
| 6.2.3 | Estimator Block | 104 |
| 6.2.4 | Filter Block | 104 |
| 6.2.5 | Tip Trajectory Design Block | 104 |
| 6.3 | Controller Details | 104 |
| 6.3.1 | Sample Detection | 104 |
| 6.3.2 | Estimation of Curvature and Heading Direction | 106 |
| 6.3.3 | Filtering | 108 |
| 6.3.4 | Tip Trajectory | 109 |
| 6.3.5 | Summary | 111 |
| 6.4 | Simulation Experiments | 112 |
| 6.5 | Conclusion and Future Work | 115 |
| | References | 116 |
| 7 | High-Bandwidth Intermittent-Contact Mode Scanning Probe Microscopy Using Electrostatically-Actuated Microcantilevers | 119 |
| | Deepak R. Sahoo, Walter Häberle, Abu Sebastian, Haralampos Pozidis, Evangelos Eleftheriou | |
| 7.1 | Introduction | 120 |
| 7.2 | SPM Setup for IC-Mode Operation | 121 |
| 7.3 | Methodology | 123 |
| 7.3.1 | Input Shaping | 124 |
| 7.3.2 | Parallel IC Operation | 126 |
| 7.3.3 | Feedback for Reliable IC Operation | 127 |

| | | |
|-----------|---|------------|
| 7.4 | Experimental Results | 129 |
| 7.5 | Conclusion | 133 |
| | References | 134 |
| 8 | Systems and Control Approach to Electro-Thermal Sensing | 137 |
| | Abu Sebastian | |
| 8.1 | Introduction | 137 |
| 8.2 | Systems Model | 138 |
| 8.3 | Electro-Thermal Topography Sensor | 142 |
| 8.4 | Electro-Thermal Position Sensor | 145 |
| 8.5 | Feedback-Enhanced Electrothermal Sensing | 148 |
| 8.6 | Conclusion | 151 |
| | References | 151 |
| 9 | Motion Controller for Atomic Force Microscopy Based Nanobiomanipulation | 153 |
| | Ning Xi, Ruiguo Yang, King Wai Chiu Lai, Bo Song, Bingtuan Gao, Jian Shi, Chanmin Su | |
| 9.1 | Introduction | 153 |
| 9.2 | System Modification and Identification | 155 |
| | 9.2.1 AFM Imaging | 156 |
| | 9.2.2 AFM Nanomanipulation | 157 |
| | 9.2.3 Hardware Modification | 157 |
| | 9.2.4 System Identification | 158 |
| 9.3 | Control Scheme Design Issues | 158 |
| | 9.3.1 Feedback Issue | 158 |
| | 9.3.2 Frequency Issue | 159 |
| | 9.3.3 Nonlinearity Issue | 159 |
| 9.4 | Design and Implementation of the Multiple-Input Single-Output System | 160 |
| | 9.4.1 Step Response Analysis | 162 |
| | 9.4.2 Continuous Input | 163 |
| 9.5 | Experimental Test of Control Scheme by a Nanobiomanipulation Task | 164 |
| | 9.5.1 Materials and Methods for Sample Preparation | 164 |
| | 9.5.2 Structural Characterization of Cell-Cell Adhesion Structure by Different Techniques | 165 |
| | 9.5.3 Experimental Setup and Results | 165 |
| 9.6 | Conclusion | 166 |
| | References | 167 |
| 10 | Nanobioscience Based on Nanorobotic Manipulation | 169 |
| | Toshio Fukuda, Masahiro Nakajima | |
| 10.1 | Introduction | 169 |
| 10.2 | Nanorobotic Manipulation System | 170 |

| | | |
|-----------|---|------------|
| 10.2.1 | Nanorobotic Manipulation System under Various Microscopes | 170 |
| 10.2.2 | Nanolaboratory Based on Nanorobotic Manipulations | 172 |
| 10.3 | Nanobioscience Applications Based on Nanorobotic Manipulations | 173 |
| 10.3.1 | Single-Cell Analysis and Nanosurgery System Based on Nanorobotic Manipulations | 173 |
| 10.3.2 | E-SEM Nanonnanorobotic Manipulation System | 175 |
| 10.3.3 | Examples for Single-Cell Manipulations Based on E-SEM Nanorobotic Manipulation System | 175 |
| 10.4 | Future Direction of Nanobioscience Applications Based on Nanorobotic Manipulations – “in vitro” Realization of “in vivo” Environment for Bio-medical Applications | 177 |
| 10.5 | Conclusion | 178 |
| | References | 178 |
| 11 | Self-configuring CMOS Microsystems | 181 |
| | Gary K. Fedder, Tamal Mukherjee, Lawrence Pileggi | |
| 11.1 | Introduction | 181 |
| 11.2 | CMOS and MEMS Integration | 182 |
| 11.3 | Reconfigurable RF MEMS Capacitors | 184 |
| 11.4 | Self-configuring MEMS Probes | 188 |
| 11.5 | Self-healing RF Microresonator Systems | 191 |
| 11.6 | Conclusions | 197 |
| | References | 199 |
| 12 | Capillary Force Actuation: A Mechatronic Perspective | 201 |
| | Carl R. Knospe | |
| 12.1 | Introduction | 201 |
| 12.1.1 | Microactuators | 201 |
| 12.1.2 | Capillary Force Actuation | 203 |
| 12.2 | Principle of Actuation | 204 |
| 12.2.1 | Electrowetting | 204 |
| 12.2.2 | Capillary Bridges | 205 |
| 12.2.3 | Equilibrium Actuator Force | 206 |
| 12.2.4 | Limiting Phenomena | 206 |
| 12.3 | Actuator Dynamics | 207 |
| 12.3.1 | Charging Dynamics | 207 |
| 12.3.2 | Fluid Model | 207 |
| 12.3.3 | Non-equilibrium Actuator Model | 208 |
| 12.3.4 | Equilibria | 209 |
| 12.4 | Alternative Configurations | 209 |
| 12.4.1 | Wetting Passive Surface Configuration | 210 |
| 12.4.2 | Pinned Passive Surface Configuration | 211 |

| | | |
|-----------|---|------------|
| 12.5 | Potential Applications | 212 |
| 12.5.1 | RF MEMS | 212 |
| 12.5.2 | Microgrippers | 214 |
| 12.5.3 | Micro-total Analysis Systems | 216 |
| 12.6 | Conclusions | 216 |
| | References | 217 |
| 13 | Control and Estimation in Force Feedback Sensors | 219 |
| | Karl Johan Åström | |
| 13.1 | Introduction | 219 |
| 13.2 | Force Balance | 220 |
| 13.3 | Design of Force Feedback Systems | 220 |
| 13.4 | Determining the Observer Gains | 223 |
| 13.5 | A Tunneling Accelerometer | 225 |
| 13.6 | The Controller | 228 |
| 13.7 | Experiments | 230 |
| 13.8 | Summary | 232 |
| | References | 232 |
| 14 | H2 Guaranteed Cost Control in Track-Following Servos | 235 |
| | Richard Conway, Jianbin Nie, Roberto Horowitz | |
| 14.1 | Introduction | 235 |
| 14.1.1 | Preliminaries | 237 |
| 14.2 | Hard Disk Drive Model | 238 |
| 14.3 | H2 Guaranteed Cost Analysis | 242 |
| 14.3.1 | Semi-definite Programming Approach | 242 |
| 14.3.2 | Riccati Equation Approach | 245 |
| 14.3.3 | Application to Hard Disk Drives | 248 |
| 14.4 | Full Information H2 Guaranteed Cost Control | 249 |
| 14.4.1 | Semi-definite Programming Approach | 250 |
| 14.4.2 | Riccati Equation Approach | 251 |
| 14.4.3 | Application to Hard Disk Drives | 254 |
| 14.5 | Output Feedback H2 Guaranteed Cost Control | 256 |
| 14.5.1 | Sequential Semi-definite Programming Approach | 256 |
| 14.5.2 | Riccati Equation and Semi-definite Programming Approach | 261 |
| 14.5.3 | Application to Hard Disk Drives | 267 |
| 14.6 | Conclusion | 269 |
| | References | 270 |
| 15 | Lateral Tape Motion and Control Systems Design in Tape Storage | 271 |
| | Angeliki Pantazi | |
| 15.1 | Introduction | 271 |
| 15.2 | System Description | 272 |

| | | |
|---------------------------|---|------------|
| 15.3 | Lateral Tape Motion | 274 |
| 15.3.1 | Stationary Periodic Components | 275 |
| 15.3.2 | Stack Shifts | 275 |
| 15.4 | Active Tape Guiding | 276 |
| 15.5 | Track-Follow Control System | 280 |
| 15.5.1 | Track-Follow Controller for Periodic Disturbances | 281 |
| 15.5.2 | Track-Follow Controller for Stack Shifts | 284 |
| 15.6 | Conclusion | 286 |
| | References | 286 |
| Author Index | | 289 |