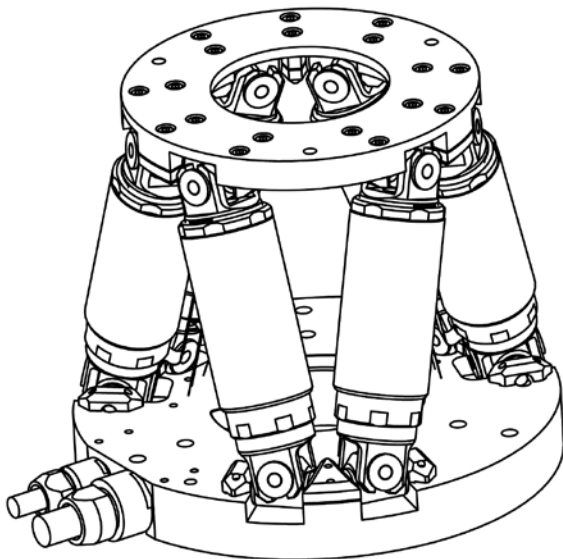


## MS199E H-811 Hexapod Microrobot User Manual

Version: 1.1.0

Date: 04.06.2013



**This document describes the following products:**

- **H-811.D1**  
Miniature-Hexapod Microrobot, Direct Drive, 10 mm/s, 5 kg Load, 2 m Cable
- **H-811.DV**  
Miniature-Hexapod Microrobot, Direct Drive, 10 mm/s, 5 kg Load, Vacuum Compatible to  $10^{-6}$  hPa, 2 m Vacuum-Side Cable, Feedthrough, 3 m Air-Side Cable



Physik Instrumente (PI) GmbH & Co. KG is the owner of the following trademarks:  
PI®, PIC®, PICMA®, PLine®, PIFOC®, PiezoWalk®, NEXACT®, NEXLINE®,  
NanoCube®, NanoAutomation®, Picoactuator®, PInano®

© 2013 Physik Instrumente (PI) GmbH & Co. KG, Karlsruhe, Germany. The text, photographs and drawings in this manual are protected by copyright. With regard thereto, Physik Instrumente (PI) GmbH & Co. KG retains all the rights. Use of said text, photographs and drawings is permitted only in part and only upon citation of the source.

Original instructions

First printing: 04.06.2013

Document number: MS199E, BRo, version 1.1.0

Subject to change without notice. This manual is superseded by any new release. The latest release is available for download (p. 3) on our website.



# Contents

<b>1</b>	<b>About this Document</b>	<b>1</b>
1.1	Goal and Target Audience of this User Manual .....	1
1.2	Symbols and Typographic Conventions .....	1
1.3	Other Applicable Documents .....	2
1.4	Downloading Manuals .....	3
<b>2</b>	<b>Safety</b>	<b>5</b>
2.1	Intended Use .....	5
2.2	General Safety Instructions .....	5
2.2.1	Organizational Measures .....	6
2.2.2	Measures for Handling Vacuum-Compatible Products .....	6
2.2.3	Safety Measures during Transport .....	6
2.2.4	Safety Measures during Installation .....	7
2.2.5	Safety Measures during Start-Up .....	8
2.2.6	Safety Measures during Maintenance .....	8
<b>3</b>	<b>Product Description</b>	<b>9</b>
3.1	Features and Applications .....	9
3.2	Model Overview .....	10
3.3	Product View .....	11
3.4	Scope of Delivery .....	12
3.5	Technical Features .....	13
3.5.1	Struts .....	13
3.5.2	Reference Point Switch and Limit Switches .....	13
3.5.3	Control .....	13
3.5.4	Motion .....	14
<b>4</b>	<b>Unpacking</b>	<b>19</b>
<b>5</b>	<b>Installation</b>	<b>23</b>
5.1	General Notes on Installation .....	23
5.2	Determining the Permissible Load and Working Space .....	24
5.3	Attaching the snap-on ferrite suppressor .....	25
5.4	Grounding the Hexapod .....	26
5.5	Mounting the Hexapod on a Surface .....	26
5.6	Affixing the Load to the Hexapod .....	28
5.7	Connecting the Cable Set for the Vacuum-Compatible Version H-811.DV .....	30

6	Start-Up	33
6.1	General Notes on Start-Up .....	33
6.2	Starting Up the Hexapod System .....	35
7	Maintenance	37
7.1	Carrying out a Maintenance Run.....	37
7.2	Packing the Hexapod for Transport.....	38
7.3	Cleaning the Hexapod .....	40
8	Troubleshooting	41
9	Customer Service	43
10	Technical Data	45
10.1	Specifications.....	45
10.1.1	Data Table .....	45
10.1.2	Maximum Ratings.....	46
10.1.3	Specifications for Vacuum-Compatible Versions .....	47
10.2	Ambient Conditions and Classifications .....	48
10.3	Dimensions .....	48
10.4	Pin Assignment.....	50
10.4.1	Power Source Connection .....	50
10.4.2	Data Transmission Connection .....	51
11	Old Equipment Disposal	55
12	Glossary	57
13	Appendix	61
13.1	Explanations of the Performance Test Sheet.....	61
13.2	EC Declaration of Conformity .....	62

# 1 About this Document

## In this Chapter

Goal and Target Audience of this User Manual .....	1
Symbols and Typographic Conventions .....	1
Other Applicable Documents .....	2
Downloading Manuals .....	3

## 1.1 Goal and Target Audience of this User Manual

This manual contains information on the intended use of the H-811.

It assumes that the reader has a fundamental understanding of basic servo systems as well as motion control concepts and applicable safety procedures.

The latest versions of the user manuals are available for download (p. 3) on our website.

## 1.2 Symbols and Typographic Conventions

The following symbols and typographic conventions are used in this user manual:

### **CAUTION**



#### **Dangerous situation**

If not avoided, the dangerous situation will result in minor injury.

- Actions to take to avoid the situation.

### **NOTICE**




#### **Dangerous situation**

If not avoided, the dangerous situation will result in damage to the equipment.

- Actions to take to avoid the situation.

### **INFORMATION**

Information for easier handling, tricks, tips, etc.

<b>Symbol/Label</b>	<b>Meaning</b>
1. 2.	Action consisting of several steps whose sequential order must be observed
➤	Action consisting of one or several steps whose sequential order is irrelevant
▪	List item
p. 5	Cross-reference to page 5
<b>RS-232</b>	Labeling of an operating element on the product (example: socket of the RS-232 interface)
	Warning sign on the product which refers to detailed information in this manual.

## 1.3 Other Applicable Documents

The devices and software tools which are mentioned in this documentation are described in their own manuals.

<b>Description</b>	<b>Document</b>
C-887 Hexapod controller	MS204E User Manual
C-887 Hexapod controller	MS204Equ User Manual Short Version

## 1.4 Downloading Manuals

### INFORMATION

If a manual is missing on our website or if there are problems in downloading:

- Contact our customer service department (p. 43).

The current versions of the manuals are found on our website. To download a manual, proceed as follows:

1. Open the website **http://www.pi-portal.ws**.
2. Click **Downloads**.
3. Click the corresponding category (e. g. **H-Hexapods**).
4. Click the corresponding product code (e. g. **H-811**).

An overview of the available file types is shown for the selected product.

5. If **(0 Files)** is shown in the **Documents** line, log in as follows to display and download the documents:
  - a) Insert the product CD in the corresponding PC drive.
  - b) Open the **Manuals** directory.
  - c) Open the Release News (e. g. **C-887\_Releasenews\_V\_x\_x\_x.pdf**) on the CD of the product.
  - d) Find the user name and password in the **User login for software download** section in the Release News.
  - e) In the **User login** area on the left margin in the website, enter the user name and the password in the corresponding fields.
  - f) Click **Login**.

If **Documents (0 Files)** is still being displayed, no manuals are available:

- Contact our customer service department (p. 43).
6. Click **Documents**.
  7. Click the desired manual and save it on the hard disk of your PC or on a data storage medium.





## 2 Safety

### In this Chapter

Intended Use .....	5
General Safety Instructions .....	5

### 2.1 Intended Use

The Hexapod microrobot (in short: "Hexapod") is a laboratory device in accordance with DIN EN 61010-1. It is intended to be used in interior spaces and in an environment that is free of dirt, oil and lubricants.

Based on its design and realization, the Hexapod is intended for positioning, adjusting and shifting of loads in six axes at various velocities.

The Hexapod is part of a Hexapod system. The intended use of the Hexapod is only possible in connection with the Hexapod controller, which is part of the Hexapod system and coordinates all motions of the Hexapod.

### 2.2 General Safety Instructions

The H-811 is built according to state-of-the-art technology and recognized safety standards. Improper use can result in personal injury and/or damage to the H-811.

- Only use the H-811 for its intended purpose, and only use it if it is in a good working order.
- Read the user manual.
- Immediately eliminate any faults and malfunctions that are likely to affect safety.

The operator is responsible for the correct installation and operation of the H-811.

## 2.2.1 Organizational Measures

### User manual

- Always keep this user manual available by the H-811.  
The latest versions of the user manuals are available for download (p. 3) on our website.
- Add all information given by the manufacturer to the user manual, for example supplements or Technical Notes.
- If you pass the H-811 on to other users, also turn over this user manual as well as other relevant information provided by the manufacturer.
- Only use the device on the basis of the complete user manual. Missing information due to an incomplete user manual can result in minor injury and property damage.
- Only install and operate the H-811 after having read and understood this user manual.

### Personnel qualification

The H-811 may only be started up, operated, maintained and cleaned by authorized and qualified staff.

## 2.2.2 Measures for Handling Vacuum-Compatible Products

When handling the vacuum version of the Hexapod, attention must be paid to appropriate cleanliness. At PI, all parts are cleaned before assembly. During assembly and measurement, powder-free gloves are worn. Afterwards, the Hexapod is cleaned once again by wiping and shrink-wrapped twice in vacuum-compatible film.

- Only touch the Hexapod with powder-free gloves.
- If necessary, wipe the Hexapod clean after unpacking.

## 2.2.3 Safety Measures during Transport

An impermissible mechanical load can damage the Hexapod.

- Only send the Hexapod in the original packaging.
- Only hold the Hexapod by the base plate.

A cable break leads to a failure of the Hexapod.

- Pack the Hexapod as to ensure that the cables are not bent or squeezed too severely.

## 2.2.4 Safety Measures during Installation

Impermissible mechanical load and collisions between the Hexapod, the load to be moved and the environment can damage the Hexapod.

- Only hold the Hexapod by the base plate.
- Before installing the load, determine the limit value for the load of the Hexapod with a simulation program (p. 24).
- Before installing the load, determine the work space of the Hexapod with a simulation program (p. 24).
- Make sure that the installed load observes the limit value determined with the simulation program.
- Avoid high forces and torques on the moving platform during installation of the Hexapod and the load.
- Ensure an uninterruptible power supply in order to prevent an unintentional deactivation of the Hexapod system and resulting unintentional position changes of the Hexapod.
- Make sure that no collisions between the Hexapod, the load to be moved and the environment are possible in the work space of the Hexapod.

Incorrect mounting can warp the base plate. Warping of the base plate reduces the accuracy.

- Mount the Hexapod on an even surface. The recommended evenness of the surface is 200  $\mu\text{m}$ .

The Hexapod can be damaged by excessively long screws.

- When selecting the screw length, observe the thickness of the moving platform (p. 48) or the depth of the mounting holes together with the load to be mounted.
- Only use screws that do not project under the moving platform after being screwed in.
- Only mount the Hexapod and a load on the mounting fixtures (holes) intended for this purpose.

### 2.2.5 Safety Measures during Start-Up

There is a risk of minor injuries caused by crushing which can occur between the moving parts of the Hexapod and a stationary part or obstacle.

- Keep your fingers away from areas where they can get caught by moving parts.

The geometrical data used by the Hexapod controller must be adapted to the Hexapod. If incorrect geometrical data is used, the Hexapod can be damaged by uncontrolled motions or collisions. The geometrical data is adapted before delivery.

- Check whether the Hexapod controller matches the Hexapod.  
A label on the rear panel of the controller indicates for which Hexapod the controller is intended.
- Only operate the Hexapod with a Hexapod controller whose geometrical data is adapted to the Hexapod.

Collisions can damage the Hexapod, the load to be moved, and the surroundings.

- Make sure that no collisions between the Hexapod, the load to be moved, and the surroundings are possible in the working space of the Hexapod.
- Do not place any objects in areas where they can get caught by moving parts.
- Immediately stop the motion if a malfunction occurs in the Hexapod controller (see user manual of the Hexapod controller).

### 2.2.6 Safety Measures during Maintenance

The Hexapod can become misaligned as a result of improper maintenance. The specifications (p. 45) can change as a result.

- Do not loosen any screws.

## 3 Product Description

### In this Chapter

Features and Applications .....	9
Model Overview .....	10
Product View .....	11
Scope of Delivery .....	12
Technical Features .....	13

### 3.1 Features and Applications

Two models of the H-811 Hexapod are available:

- The directly driven H-811.D1 model is **not** vacuum-compatible.
- The directly driven H-811.DV model is vacuum-compatible.

Both models achieve a velocity of up to 10 mm/s and a load capacity of 5 kg in vertical orientation and 2.5 kg in any orientation.

The parallel kinematics structure and the free choice of the pivot point offer the following advantages:

- Positioning operations in six independent axes (three translation axes, three rotation axes) with short settling times
- Pivot point is maintained for rotations and moves along with linear motions
- High accuracy and step resolution in all axes
- No addition of the errors of individual axes
- No friction and torques from moving cables

The Hexapod is controlled with the Hexapod controller, which is part of the Hexapod system. The position commands to the Hexapod controller are entered in Cartesian coordinates.

## 3.2 Model Overview

Hexapod and Hexapod controller are only available together as a system.

### Possible system components

Standard versions of the H-811 Hexapod:

Model	Name
H-811.D1	Miniature-Hexapod Microrobot, Direct Drive, 10 mm/s, 5 kg Load, 2 m Cable (permanently installed)
H-811.DV	<p>Miniature Hexapod Microrobot, Direct Drive, 10 mm/s, 5 kg Load, Vacuum-Compatible to <math>10^{-6}</math> hPa, 2 m Cable on the Vacuum Side (permanently installed), Vacuum Feedthrough, 3 m Cable on the Air Side.</p> <p>Details on vacuum feedthroughs and cables on the air side:</p> <ul style="list-style-type: none"> <li>▪ Vacuum feedthrough for data transmission, HD Sub-D 78m/f (4668)</li> <li>▪ Vacuum feedthrough for power source, LEMO 2-pin to M12m (C887B0002)</li> <li>▪ Data transmission cable on the air side, HD Sub-D 78f to MDR68m, 3 m (K040B0092)</li> <li>▪ Power supply cable on the air side, M12m to M12f, 3 m (K060B0112)</li> </ul>

Standard versions of the C-887 Hexapod controller:

Model	Name
C-887.11	6-D Hexapod Controller, Control of 2 Additional Servo-Motor Axes Included, TCP/IP and RS-232 Interface, 19" Chassis
C-887.21	6-D Hexapod Controller, TCP/IP and RS-232 Interface, Bench-Top

### Available Hexapod systems

The following Hexapod systems are available as combinations of Hexapod and Hexapod controller:

System	Hexapod including cable set		Hexapod Controller	
	H-811.D1	H-811.DV	C-887.11	C-887.21
–			C-887.11	C-887.21
H-811.D11	X	–	X	–
H-811.D12	X	–	–	X
H-811.DV1	–	X	X	–
H-811.DV2	–	X	–	X

### 3.3 Product View

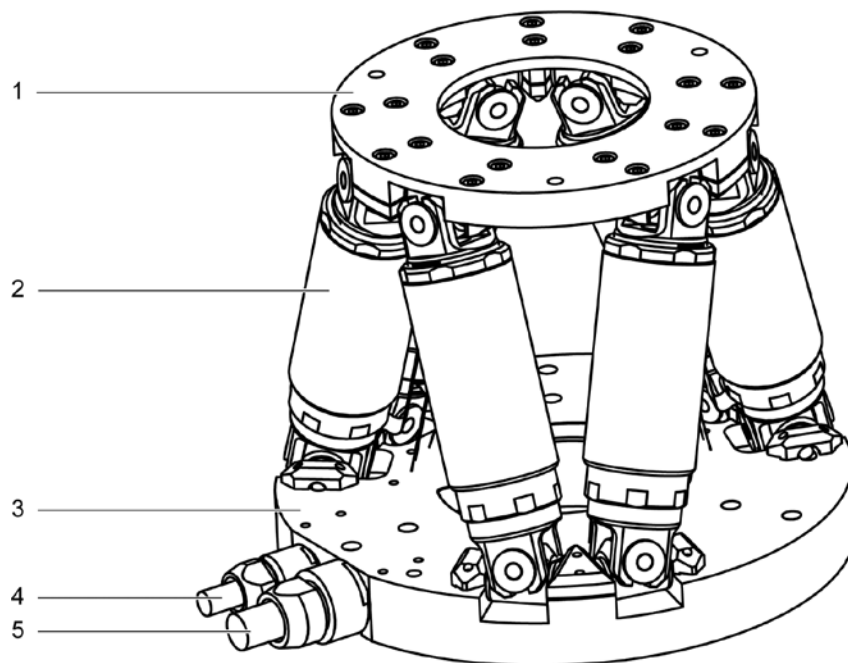


Figure 1: Product view

- 1 Moving platform
- 2 Strut
- 3 Base plate
- 4 Power supply cable
- 5 Data transmission cable

### 3.4 Scope of Delivery

The following table contains the scope of delivery of the Hexapod.

The scope of delivery of the Hexapod controller is listed in the user manual of the Hexapod controller.

Order Number	Items
H-811	Hexapod according to your order (p. 10)
Cable Set	See list of standard versions of the H-811 Hexapod in "Model Overview" (p. 10)
000015165	Steward snap-on ferrite suppressor
Packaging, consisting of:	
	<ul style="list-style-type: none"> <li>▪ Outer box</li> <li>▪ Inner box</li> <li>▪ Two pads for sliding onto the inner box</li> <li>▪ Internal cushion, bottom</li> <li>▪ Internal cushion, cover</li> <li>▪ Pallet</li> </ul>
Documentation, consisting of:	
H811T0001	Technical Note on unpacking the Hexapod
MS199E	User manual for the Hexapod (this document)
Screw sets:	
000020110	Mounting accessories: <ul style="list-style-type: none"> <li>▪ 6 M4x25 hex-head cap screws ISO 4762</li> <li>▪ 1 Allen wrench 3.0 DIN 911</li> </ul>
000036450	Accessories for connection to the grounding system: <ul style="list-style-type: none"> <li>▪ 1 flat-head screw with cross recess M4x8 ISO 7045</li> <li>▪ 2 washers, form A-4.3 DIN 7090</li> <li>▪ 2 safety washers, Schnorr Ø 4 mm N0110</li> </ul>



## 3.5 Technical Features

### 3.5.1 Struts

The Hexapod has six adjustable-length struts. Each strut carries out linear motions. Each set of settings of the six struts defines a position of the moving platform in six degrees of freedom (three translational axes and three rotational axes).

Each strut is equipped with the following components:

- One actuator
- Reference and limit switches
- Joints for connecting to the base plate and moving platform

The actuator contains a direct drive, consisting of DC motor with rotary encoder and drive screw.

### 3.5.2 Reference Point Switch and Limit Switches

The reference point switch of a strut functions independently of the angular positions of the strut ends and the lengths of the other struts.

When a limit switch is activated, the power source of the motor is switched off to protect the Hexapod against damage from malfunctions.

### 3.5.3 Control

The Hexapod is intended for operation with the Hexapod controller which belongs to the Hexapod system. The Hexapod controller makes it possible to command motion of individual axes, combinations of axes or all six axes at the same time in a single motion command.

The Hexapod controller calculates the settings for the individual struts from the target positions given for the translational and rotational axes. The velocities and accelerations of the struts are calculated in such a way that all struts start and stop at the same time.

After the Hexapod controller has been switched on or restarted, the Hexapod has to complete a reference move in which each strut moves to its reference point switch. After the reference move, the moving platform is in the reference position and can be commanded to move to absolute target positions.

For more information, see the user manual of the Hexapod controller.

### 3.5.4 Motion

The platform moves along the translational axes X, Y and Z and around the rotational axes U, V and W.

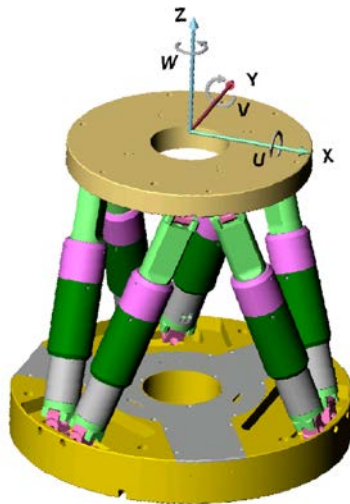


Figure 2: XYZ coordinate system and rotations to the rotation coordinates U, V and W. The coordinate system is depicted above the platform for better clarity.

#### Translation

Translations are described in the spatially-fixed XYZ coordinate system. The translational axes meet at the origin of the XYZ coordinate system (0,0,0). For more information, see the glossary (p. 57).

#### Rotation

Rotations take place around the rotational axes U, V and W. The rotational axes meet at the pivot point. For more information on the pivot point, see the glossary (p. 57).

In contrast to the spatially-fixed translational axes, the rotational axes and thus the pivot point as well move along with the platform (see also the example below for consecutive rotations).

A given rotation in space is calculated from the individual rotations in the sequence  $U > V > W$ .

**INFORMATION**

The dimensional drawing (p. 48) contains the following:

- Alignment of the XYZ coordinate system
- Position of the pivot point after the reference move, when the standard settings of the Hexapod controller are used

**Example: Consecutive rotations****INFORMATION**

For a clearer view, the figures have been adapted as follows:

- Round platform replaced by T-shaped platform
- XYZ coordinate system shown shifted
- Pivot point in the top left corner of the platform

1. The U axis is commanded to move to position 10.

The rotation around the U axis tilts the rotational axes V and W.

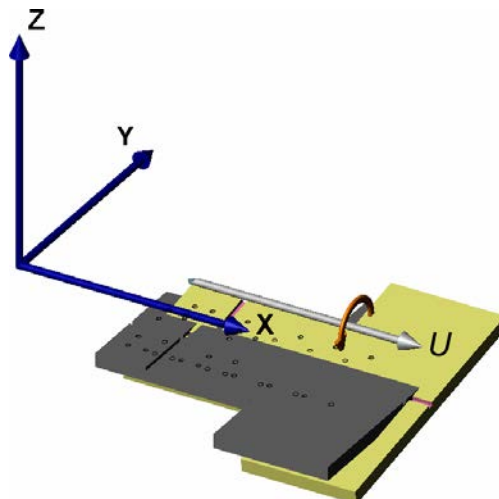


Figure 3: Rotation around the U axis

- Platform in reference position
- Platform position: U = 10 (U parallel to spatially-fixed X axis)

2. The V axis is commanded to move to position  $-10$ .

The rotation takes place around rotational axis V, which was tilted during the previous rotation.

The rotation around the V axis tilts the rotational axes U and W.

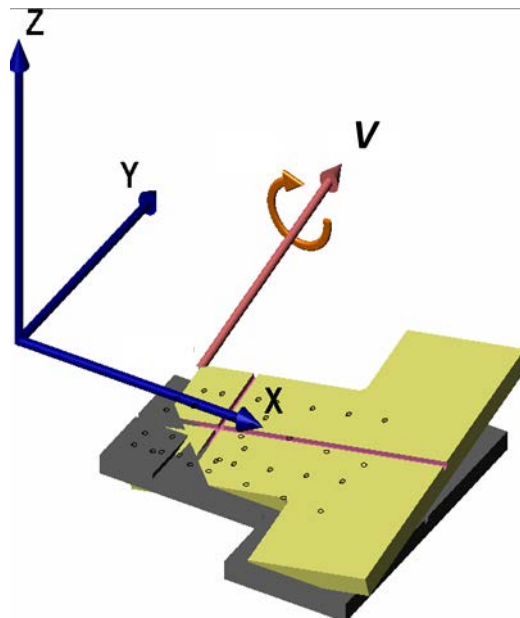


Figure 4: Rotation around the V axis

- Platform in reference position
- Platform position:  $U = 10$ ,  $V = -10$  (U and V parallel to the platform level)

- The W axis is commanded to move to position 10.

The rotation takes place around the rotational axis W, which was tilted during the previous rotations. The W axis is always vertical to the platform level.

The rotation around the W axis tilts the rotational axes U and V.

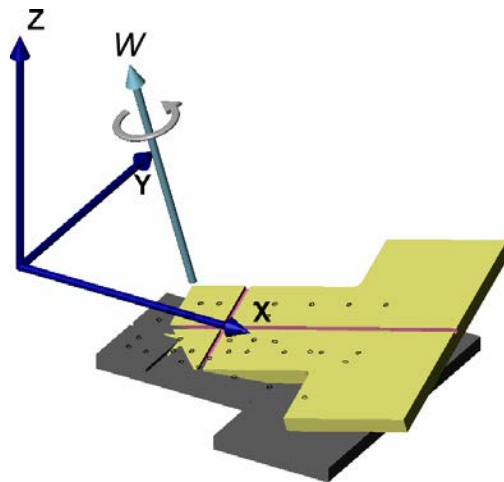


Figure 5: Rotation around the W axis

- Platform in reference position
- Platform position:  $U = 10$ ,  $V = -10$ ,  $W = 10$  (U and V parallel to the platform level, W vertical to the platform level)

For more data on the travel ranges, see the "Specifications" section (p. 45).



## 4 Unpacking

The Hexapod is delivered in a special packaging with adapted foam inserts.

### NOTICE



#### Impermissible mechanical load!

An impermissible mechanical load can damage the Hexapod.

- Only send the Hexapod in the original packaging.
- Only hold the Hexapod by the base plate.

### INFORMATION

When handling the vacuum version of the Hexapod, attention must be paid to appropriate cleanliness. At PI, all parts are cleaned before assembly. During assembly and measurement, powder-free gloves are worn. Afterwards, the Hexapod is cleaned once again by wiping and shrink-wrapped twice in vacuum-compatible film.

- Only touch the Hexapod with powder-free gloves.
- If necessary, wipe the Hexapod clean after unpacking.

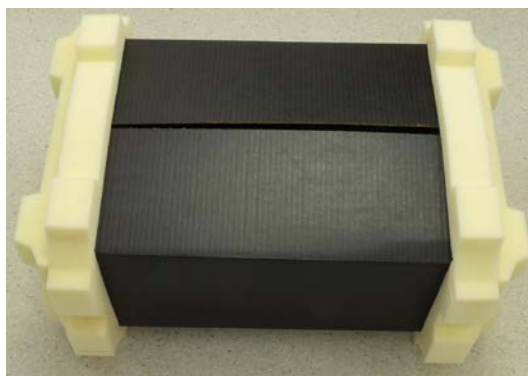
### Unpacking the Hexapod

1. Open the outer box.



Figure 6: Outer box with inner box

2. Lift the inner box with the side pads out of the outer box.



*Figure 7: Inner box with side pads*

3. Remove the side pads.
4. Open the inner box.



*Figure 8: Foam cover in the inner box*

5. Remove the foam cover.



*Figure 9: Hexapod and cables in the inner box*



6. Hold the Hexapod by the base plate and take it out of the foam insert.
7. Compare the contents against the items covered by the contract and against the packing list. If parts are incorrectly supplied or missing, contact PI immediately.
8. Inspect the Hexapod for signs of damage. If you notice signs of damage, contact PI immediately.
9. Keep all packaging materials in case the product needs to be transported again later.



## 5 Installation

### In this Chapter

General Notes on Installation .....	23
Determining the Permissible Load and Working Space .....	24
Attaching the snap-on ferrite suppressor .....	25
Grounding the Hexapod .....	26
Mounting the Hexapod on a Surface .....	26
Affixing the Load to the Hexapod .....	28

### 5.1 General Notes on Installation

The Hexapod can be mounted in any orientation.

#### NOTICE



#### Impermissible mechanical load and collisions!

Impermissible mechanical load and collisions between the Hexapod, the load to be moved and the environment can damage the Hexapod.

- Only hold the Hexapod by the base plate.
- Before installing the load, determine the limit value for the load of the Hexapod with a simulation program (p. 24).  
The limit values determined with the simulation program are only valid when the Hexapod controller has the servo mode switched on for the axes of the moving platform of the connected Hexapod.
- Before installing the load, determine the working space of the Hexapod with a simulation program (p. 24).  
The limits of the working space vary depending on the current position of the Hexapod (translation and rotation coordinates) and the current coordinates of the pivot point.
- Avoid high forces and torques on the moving platform during installation.
- Ensure an uninterruptible power supply in order to prevent an unintentional deactivation of the Hexapod system and resulting unintentional position changes of the Hexapod.
- Make sure that no collisions between the Hexapod, the load to be moved and the environment are possible in the working space of the Hexapod.

### INFORMATION

The optionally available PIVeriMove software for collision checking can be used to mathematically check possible collisions between the Hexapod, the load and the environment. The use of the software is recommended when the Hexapod is located in a limited installation space and/or operated with a spatially limiting load. For details regarding the activation and configuration of the PIVeriMove software for collision checking, see Technical Note C887T0002 (included in the scope of delivery of the software).

## 5.2 Determining the Permissible Load and Working Space

### Tools and accessories

- PC with Windows operating system on which the simulation program Hexapod Simulation Software is installed. For more information, see the manual of the Hexapod controller.

### Determining the working space and permissible load of the Hexapod

- Follow the instructions in the manual of the Hexapod controller to determine the working space and the limit value for the load of the Hexapod with the simulation program.

The limit values in the following table are for orientation. They only apply when the center of mass is at the origin of the XYZ coordinate system (0,0,0).

Mounting position of the base plate	Servo mode switched on for Hexapod – max. load capacity		Servo mode switched off for Hexapod – max. holding force	
	Mounted horizontally	Mounted as desired	Mounted horizontally	Mounted as desired
H-811.D1	5 kg	2.5 kg	15 N	2.5 N
H-811.DV	5 kg	2.5 kg	15 N	2.5 N

If you need help in determining the limit value for the load or determining the work space:

- Contact our customer service department (p. 43).

## 5.3 Attaching the snap-on ferrite suppressor



Figure 10: Power supply cable of the Hexapod with snap-on ferrite suppressor

- 1 Power supply cable of the Hexapod
- 2 Snap-on ferrite suppressor 000015165
- 3 Connector M 12 (for connection to the controller)

### INFORMATION

The snap-on ferrite suppressor 000015165 is included in the scope of delivery of the Hexapod system. The snap-on ferrite suppressor is for permanent attachment to the power supply cable of the Hexapod. The snap-on ferrite suppressor ensures the electromagnetic compatibility of the Hexapod system.

- When attaching the snap-on ferrite suppressor, make sure that it is correctly positioned on the cable. The snap-on ferrite suppressor can only be removed with special tools (not included in the scope of delivery).
- Attach the snap-on ferrite suppressor to the power supply cable of the Hexapod before you connect the Hexapod to the Hexapod controller for the first time.

### Tools and accessories

- Snap-on ferrite suppressor 000015165, in the scope of delivery (p. 12)

### Permanently attaching the snap-on ferrite suppressor

1. Place the power supply cable of the Hexapod close behind the M12 connector, that is intended for connection to the controller, into the opened snap-on ferrite suppressor (see figure).
2. Close the snap-on ferrite suppressor:
  - a) Align the cable so that it is not squeezed when the snap-on ferrite suppressor is closed.
  - b) Carefully press the two halves of the snap-on ferrite suppressor around the cable until the lock engages.

## 5.4 Grounding the Hexapod

If a functional grounding is required for potential equalization:

1. Connect the base plate to the grounding system:
  - For connection, use the supplied accessories (p. 12) and the M4 hole with an 8 mm depth marked with the ground connection symbol (p. 48).
2. Connect the moving platform to the grounding system:
  - Use one of the mounting holes in the moving platform (p. 48) for connection.  
or
  - If the moving platform and the load are conductively connected with each other, connect the load to the grounding system.

## 5.5 Mounting the Hexapod on a Surface

### NOTICE



#### Impermissible mechanical load!

An impermissible mechanical load can damage the Hexapod.

- Only hold the Hexapod by the base plate.

### NOTICE



#### Warping of the base plate!

Incorrect mounting can warp the base plate. Warping of the base plate reduces the accuracy.

- Mount the Hexapod on an even surface. The recommended evenness of the surface is 200 µm.

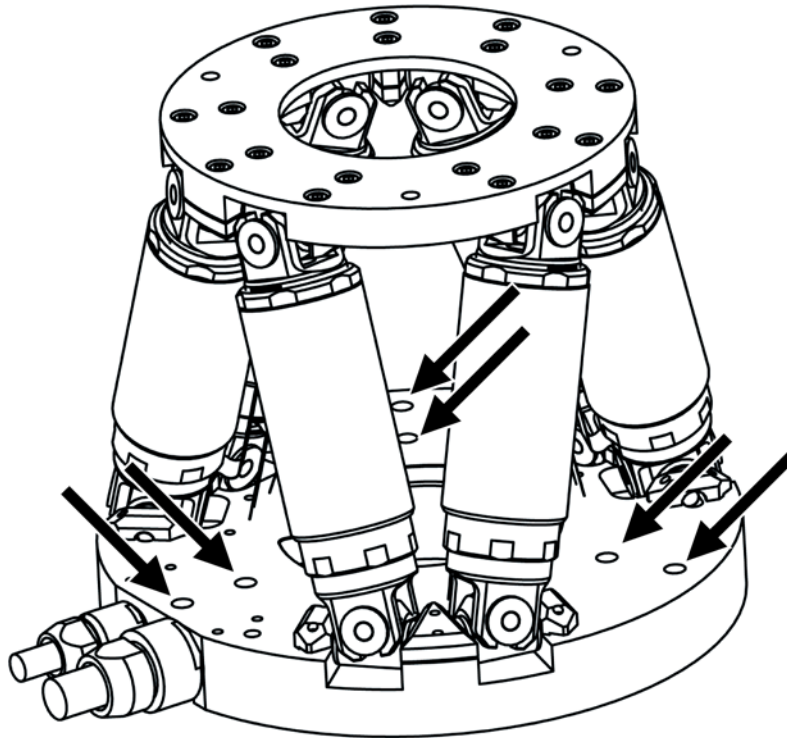


Figure 11: Mounting holes in the base plate

### Prerequisite

- ✓ You have read and understood the General Notes on Installation (p. 23).

### Tools and accessories

- Allen wrench 3.0 and six of the supplied M4x25 screws (p. 12)

### Mounting the Hexapod

1. Provide six M4 threaded holes in the support for mounting with M4x25 screws.  
The arrangement of the six mounting holes can be found in the upper figure or in the dimensional drawing (p. 48).
2. Mount the Hexapod on the six mounting holes in the base plate using the included M4x25 screws.

## 5.6 Affixing the Load to the Hexapod

### NOTICE



#### Impermissible mechanical load and collisions!

Impermissible mechanical load and collisions between the Hexapod, the load to be moved, and the environment can damage the Hexapod.

- Make sure that the installed load observes the limit value resulting from the load test (p. 24).
- Avoid high forces and torques on the moving platform during installation.
- Make sure that no collisions between the Hexapod, the load to be moved and the environment are possible in the work space of the Hexapod.

### NOTICE



#### Screws that are too long!

The Hexapod can be damaged by excessively long screws.

- When selecting the screw length, observe the thickness of the moving platform or the depth of the mounting holes (p. 48) together with the load to be mounted.
- Only use screws that do not project under the moving platform after being screwed in.
- Only mount the Hexapod and the load on the mounting fixtures (holes) intended for this purpose.



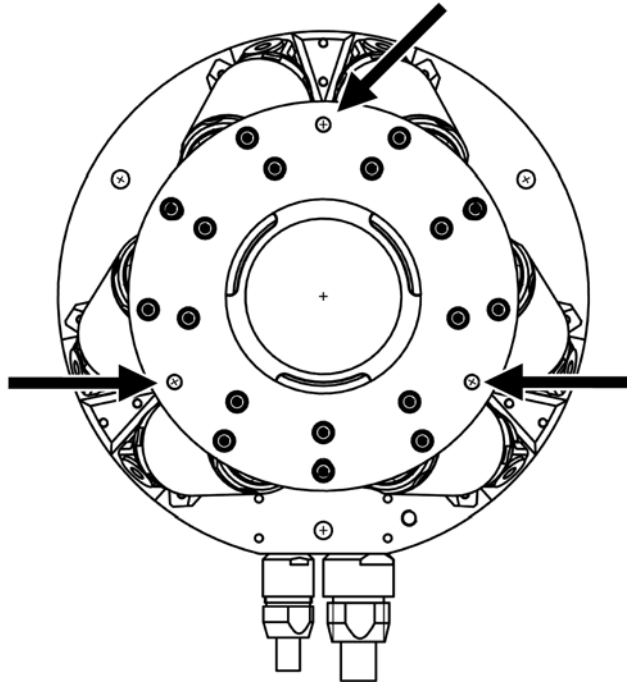


Figure 12: Mounting holes in the moving platform

### Prerequisites

- ✓ You have read and understood the General Notes on Installation (p. 23).
- ✓ You have determined the permissible load and the work space of the Hexapod (p. 24).
- ✓ You have designed the load and the environment of the Hexapod so that the permissible load of the Hexapod is observed and no collisions can occur.

### Tools and accessories

- 3 suitably long M4 screws
- Suitable tools for fastening the screws

### Affixing the Load

1. Choose the mounting position so that the selected through holes in the moving platform (see upper figure and p. 48) can be used for affixing the load.
2. Affix the load to the moving platform using the screws.

### 5.7 Connecting the Cable Set for the Vacuum-Compatible Version H-811.DV

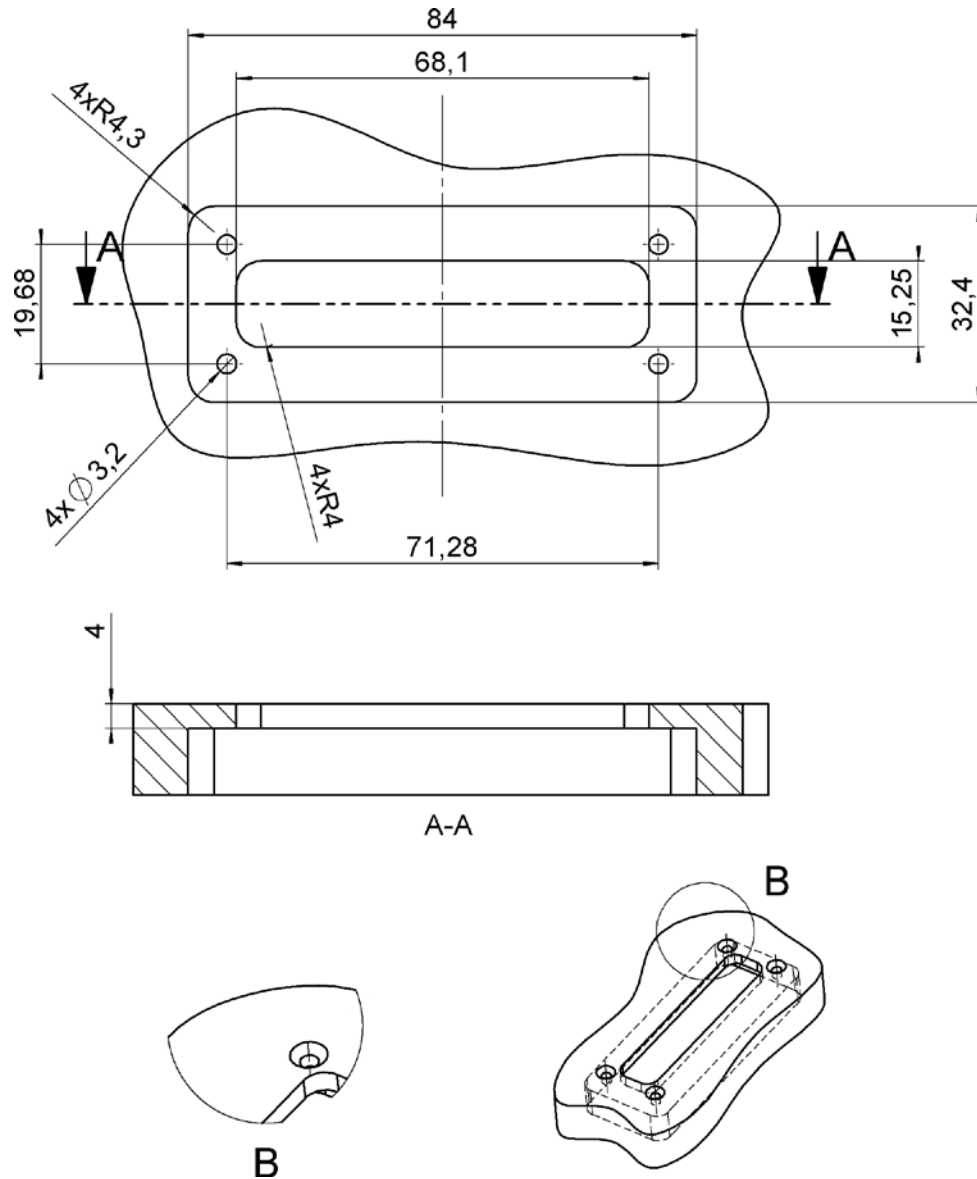


Figure 13: Dimensions of the vacuum feedthrough for data transmission (4668) (dimensions in mm)

B 4 holes 45°xØ6 for M3 countersunk screw

### Prerequisites

- ✓ The cable set is **not** connected to the Hexapod controller.

### Tools and accessories

- Vacuum feedthroughs and cables on the air side that belong to the Hexapod system (p. 10)
- Suitable tools for installing the vacuum feedthroughs

### Installing vacuum feedthroughs

1. Install the vacuum feedthrough for data transmission (4668):
  - a) See the above figure for the dimensions of the vacuum feedthrough.
  - b) Provide the vacuum chamber with a suitable opening.
  - c) Install the vacuum feedthrough so that the HD Sub-D socket 78f is in the vacuum chamber.
2. Install the vacuum feedthrough for the power source (C887B002):
  - a) Provide the vacuum chamber with an opening of 12 mm in diameter. The flange must not be more than 28 mm thick.
  - b) Install the vacuum feedthrough so that the LEMO connection is in the vacuum chamber.

### Connecting the Hexapod to vacuum feedthroughs

- Connect the cables that belong to the Hexapod system (p. 10) and the vacuum feedthroughs with each other as shown in the connection diagram below.
  - Observe the assignment that is specified by the labeling on the sockets, connectors and cables.
  - Observe the mechanical coding of connectors and sockets.
  - Do not use force.
- Do **not** connect the cables to the Hexapod controller yet.

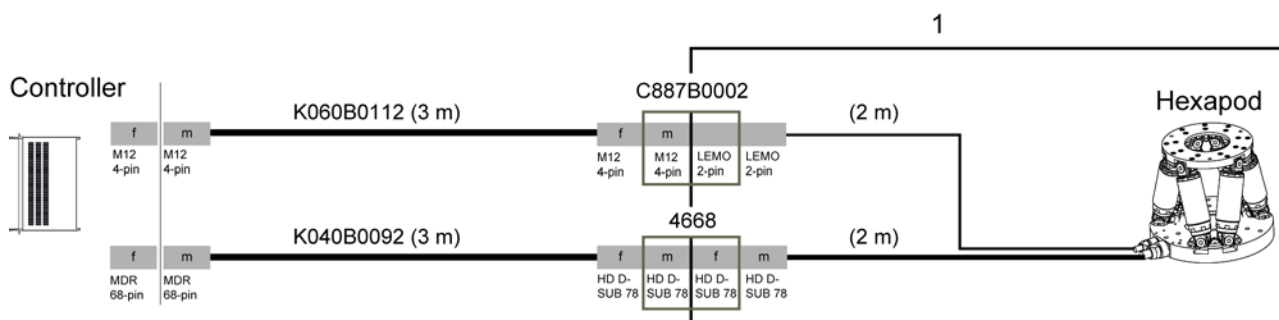


Figure 14: Cable set connection diagram for vacuum-compatible version

- K060B0112*      *Power supply cable on the air side, M12m to M12f, 3 m*
- K040B0092*      *Data transmission cable on the air side, HD Sub-D 78f to MDR68m, 3 m*
- C887B0002*      *Vacuum feedthrough for power supply, LEMO 2-pin to M12m*
- 4668*              *Vacuum feedthrough for data transmission, HD Sub-D 78m/f*
- 1*                    *Vacuum chamber*

## 6 Start-Up

### In this Chapter

General Notes on Start-Up .....	33
Starting Up the Hexapod System .....	35

### 6.1 General Notes on Start-Up

#### CAUTION



##### Risk of crushing by moving parts!

There is a risk of minor injuries caused by crushing which can occur between the moving parts of the Hexapod and a stationary part or obstacle.

- Keep your fingers away from areas where they can get caught by moving parts.

#### NOTICE



##### Incorrect configuration of the Hexapod controller!

The configuration data used by the Hexapod controller (e. g. geometrical data and servo-control parameters) must be adapted to the Hexapod. If incorrect configuration data is used, the Hexapod can be damaged by uncontrolled motions or collisions. The configuration data is adapted before delivery.

- Check whether the Hexapod controller matches the Hexapod. A label on the rear panel of the controller indicates for which Hexapod the controller is intended.
- When you have established the communication via TCP/IP or RS-232 or use the user interface of the C-887, send the `CST?` command. The response shows the Hexapod to which the controller is adapted.
- Only operate the Hexapod with a Hexapod controller whose configuration data is adapted to the Hexapod.

**NOTICE****Damage from collisions!**

Collisions can damage the Hexapod, the load to be moved, and the environment.

- Make sure that no collisions between the Hexapod, the load to be moved and the environment are possible in the work space of the Hexapod.
- Do not place any objects in areas where they can get caught by moving parts.
- If the Hexapod controller malfunctions, stop the motion immediately.

**NOTICE****Damage from unintentional position changes!**

The self-locking of the Hexapod struts is very low. Although the installed load observes the limit value resulting from the load test (p. 24), it can cause an unintentional position change of the Hexapod when the servo mode or the Hexapod controller is switched off and one of the following conditions is also fulfilled:

- The Hexapod is **not** mounted with a horizontally oriented base plate but in any other orientation.
- The Hexapod is mounted with a horizontally oriented base plate and is **not** in the reference position.

As a result of unintentional position changes, the actuators in the Hexapod struts can be damaged, and collisions between the Hexapod, the load to be moved and the environment are possible. Collisions can damage the Hexapod, the load to be moved, or the environment.

- Suitably support the moving platform or the load when the servo mode or the Hexapod controller is switched off.

## 6.2 Starting Up the Hexapod System

### Prerequisite

- ✓ You have read and understood the General Notes on Start-Up (p. 33).
- ✓ You have correctly installed the Hexapod, i.e. you have mounted the Hexapod on a surface and affixed the load to the Hexapod according to the instructions in "Installation" (p. 23).
- ✓ You have read and understood the user manual of the Hexapod controller.

### Accessories

- Hexapod controller belonging to the Hexapod system
- PC with suitable software (see user manual of the Hexapod controller)

### Starting up the Hexapod system

1. Connect the Hexapod to the Hexapod controller (see user manual of the Hexapod controller).
2. Start up the Hexapod controller (see user manual of the Hexapod controller).
3. Operate a few motion cycles for testing purposes (see user manual of the Hexapod controller).





## 7 Maintenance

### In this Chapter

Carrying out a Maintenance Run.....	37
Packing the Hexapod for Transport.....	38
Cleaning the Hexapod.....	40

#### NOTICE



#### Damage due to improper maintenance!

The Hexapod can become misaligned as a result of improper maintenance. The specifications can change as a result (p. 45).

- Only loosen screws according to the instructions in this manual.

Depending on the operational conditions and the period of use of the Hexapod, the following maintenance measures are required.

### 7.1 Carrying out a Maintenance Run

Frequent motions over a limited travel range can cause the lubricant to be unevenly distributed on the drive screw.

- Carry out a maintenance run over the entire travel range at regular intervals (see user manual of the Hexapod controller). The more often motions are carried out over a limited travel range, the shorter the time between the maintenance runs has to be.

## 7.2 Packing the Hexapod for Transport

### NOTICE



#### Impermissible mechanical load!

An impermissible mechanical load can damage the Hexapod.

- Only send the Hexapod in the original packaging.
- Only hold the Hexapod by the base plate.

### NOTICE



#### Damage from applying high forces!

Hexapod struts with direct drive can be carefully moved by hand in the case of an error. Blocked struts can be damaged by the use of force.

- If one or more struts of the Hexapod are blocked, do **not** move the Hexapod by hand.
- If you move the Hexapod by hand, do not use high forces.

### NOTICE



#### Cable break!

A cable break leads to a failure of the Hexapod.

- Pack the Hexapod as to ensure that the cables are not bent or squeezed too severely.

### Accessories

- Original packaging (p. 12)
- 4 cable ties

### Packing the Hexapod

1. Command a motion of the Hexapod to the transport position:  
 $X = Y = Z = U = V = W = 0$
2. Uninstall the Hexapod system:
  - a) Remove the load from the moving platform of the Hexapod.
  - b) Power down the Hexapod controller.

- c) Remove the data transmission cable and the power supply cable from the Hexapod controller.
  - d) Loosen the six M4x25 screws with which the Hexapod is mounted on the surface.
  - e) Remove the six M4x25 screws.
3. Prepare the cables on the Hexapod for packing. Avoid forming a kink in the cables:
    - Wind the power supply cable with a diameter of approx. 23 cm and secure it with two cable ties.
    - Wind the data transmission cable with a diameter of approx. 23 cm and secure it with two cable ties.
  4. Pack the Hexapod in a plastic film to protect it against dirt.
  5. Pack the cables of the vacuum version in a plastic film to protect them against dirt.
  6. Open the outer box.
  7. Lift the inner box with the side pads out of the outer box.
  8. Remove the side pads from the inner box.
  9. Open the inner box.
  10. Remove the foam cover.
  11. Hold the Hexapod by the base plate and place the Hexapod and the cables in corresponding recesses in the foam insert of the inner box.



Figure 15: Hexapod and cables in the inner box

12. Insert the foam cover in the inner box.
13. Close the inner box.
14. Slide the side pads onto the inner box.

15. Place the inner box with the side pads in the outer box.
16. Close the outer box.
17. Secure the box on the pallet.

## 7.3 Cleaning the Hexapod

### Prerequisites

- ✓ You have disconnected the Hexapod from the controller.

### Cleaning the Hexapod

- Do **not** use any organic solvents.

Only when the Hexapod is **not** used in vacuum:

- When necessary, clean the surfaces of the Hexapod with a cloth slightly dampened with a mild cleanser or disinfectant.

Only when the Hexapod is used in vacuum:

- Only touch the Hexapod with powder-free gloves.
- If necessary, wipe the Hexapod clean.

## 8 Troubleshooting

Problem	Possible Causes	Solution
Unexpected Hexapod behaviour.	<ul style="list-style-type: none"> <li>▪ Cable broken</li> <li>▪ Connector or soldered joints loosened</li> </ul>	<ul style="list-style-type: none"> <li>➤ Check the data transmission and power supply cables.</li> <li>➤ Replace the cables by cables of the same type and test the function of the Hexapod.</li> <li>➤ Contact our customer service department (p. 43).</li> </ul>
The Hexapod does not achieve the specified accuracy.	Warped base plate	➤ Mount the Hexapod on an even surface (p. 26). The recommended evenness of the surface is 200 µm.
	Increased wear due to small motions over a long period of time	➤ Carry out a maintenance run over the entire travel range (p. 37).
The Hexapod does not move.	<ul style="list-style-type: none"> <li>▪ Worn drive screw</li> <li>▪ Foreign body has entered the drive screw</li> <li>▪ Faulty motor</li> <li>▪ Blocked or broken joint</li> <li>▪ Dirty encoder</li> </ul>	<ul style="list-style-type: none"> <li>➤ Carry out a strut test (see user manual of the Hexapod controller). The strut test should be carried out in the reference position, unless the malfunction occurs with maximum or minimum displacement of the platform in Z.</li> <li>➤ Contact our customer service department (p. 43).</li> </ul>

If the problem with your Hexapod is not listed in the table or cannot be solved as described, contact our customer service department (p. 43).



## 9 Customer Service

For inquiries and orders, contact your PI sales engineer or send us an e-mail (<mailto:info@pi.ws>).

If you have questions concerning your system, have the following information ready:

- Product codes and serial numbers of all products in the system
- Firmware version of the controller (if present)
- Version of the driver or the software (if present)
- Operating system on the PC (if present)

The latest versions of the user manuals are available for downloading (p. 3) on our website.





## 10 Technical Data

### In this Chapter

Specifications .....	45
Ambient Conditions and Classifications .....	48
Dimensions .....	48
Pin Assignment.....	50

## 10.1 Specifications

### 10.1.1 Data Table

	H-811.D1x	Unit	Tolerance
Active axes	X, Y, Z, $\theta_x$ , $\theta_y$ , $\theta_z$		
<b>Motion and positioning</b>			
Travel range* X, Y, Z	$\pm 17$ , $\pm 16$ , $\pm 6.5$	mm	
Travel range* $\theta_x$ , $\theta_y$ , $\theta_z$	$\pm 10$ , $\pm 10$ , $\pm 21$	°	
Single-actuator design resolution	40	nm	
Min. incremental motion X, Y	0.5	$\mu\text{m}$	typ.
Min. incremental motion Z	0.2	$\mu\text{m}$	typ.
Min. incremental motion $\theta_x$ , $\theta_y$ , $\theta_z$	3.5	$\mu\text{rad}$	typ.
Backlash X, Y	1	$\mu\text{m}$	typ.
Backlash Z	0.2	$\mu\text{m}$	typ.
Backlash $\theta_x$ , $\theta_y$	10	$\mu\text{rad}$	typ.
Backlash $\theta_z$	15	$\mu\text{rad}$	typ.
Repeatability X, Y	$\pm 0.3$	$\mu\text{m}$	typ.
Repeatability Z	$\pm 0.1$	$\mu\text{m}$	typ.
Repeatability $\theta_x$ , $\theta_y$	$\pm 4$	$\mu\text{rad}$	typ.
Repeatability $\theta_z$	$\pm 8$	$\mu\text{rad}$	typ.
Max. velocity X, Y, Z	10	mm/s	
Max. velocity $\theta_x$ , $\theta_y$ , $\theta_z$	250	mrad/s	
Typ. velocity X, Y, Z	5	mm/s	
Typ. velocity $\theta_x$ , $\theta_y$ , $\theta_z$	120	mrad/s	

<b>Mechanical properties</b>			
Stiffness X, Y	0.2	N/μm	
Stiffness Z	3.6	N/μm	
Load (base plate horizontal / any orientation)	5 / 2.5	kg	max.
Holding force, de-energized (base plate horizontal / any orientation)	15 / 2.5	N	max.
Motor type	Brushless DC motor		
<b>Miscellaneous</b>			
Operating temperature range	0 to 50	°C	
Material	Stainless steel, aluminum		
Mass	2.2	kg	±5%
Cable length	2	m	±10 mm

Order as a system including controller and software. Add number 1 or 2 to the order number: H-811.xx1 for C-887.11; H-811.xx2 for C-887.21.




Technical data specified at 20±3°C.

Ask about custom designs!

\* The travel ranges of the individual coordinates (X, Y, Z, θ<sub>x</sub>, θ<sub>y</sub>, θ<sub>z</sub>) are interdependent. The data for each axis in this table shows its maximum travel, where all other axes are at their zero positions. If the other linear or rotational coordinates are not zero, the available travel may be less.

### 10.1.2 Maximum Ratings

The Hexapod is designed for the following operating data:

<b>Maximum operating voltage</b> 	<b>Maximum operating frequency (unloaded)</b> 	<b>Maximum current consumption</b> 
24 V DC	---	5 A

### 10.1.3 Specifications for Vacuum-Compatible Versions

<b>Drive and sensor</b>	
Motor	Brushless, three-phase torque motor vacuum-compatible version with gold-plated pin contacts
Gearhead	Direct drive
Encoder	Optical encoder, vacuum-compatible
Reference point switch	Optical, vacuum-compatible
Limit switches	Optical, vacuum-compatible
<b>Materials used</b>	
Machine-made parts	>95% of the machine-made parts, i.e. base plate, struts, moving platform: AlMgSi (3.2315) and AlMg4.5Mn (3.3547) chemically nickel-plated, stainless steel type 303 (1.4305) Remaining parts, e.g. coupling elements: Various vacuum-compatible materials
Bearing	Stainless steel
Drivetrain elements	Stainless steel (drive screw)
Electrical components	Cable insulation: PTFE, FEP Shrink tubing: Kynar Solder: Sn95.5Ag3.8Cu0.7 PCB (main board) Flexible printed circuit board (limit switch, pulse width modulation) Aramid insulating paper Polyimide film strip Connector: DD78 (Positronic), type FFA (LEMO)
Grease	Brayco 815Z (Micronic)
Sealing compound and adhesive	Torr seal (Varian), TRA-CAST 3145, Araldite 2014-1 (Huntsmann), 5 Minute Epoxy (Devcon)
<b>Other</b>	
Bakeout temperature	80 °C (176 °F)

## 10.2 Ambient Conditions and Classifications

Degree of pollution:	2
Transport temperature:	-25°C to +85°C
Storage temperature:	0 °C to 70 °C
Humidity:	Maximum relative humidity of 80% at temperatures of up to 31°C, linearly decreasing until relative humidity of 50% at 40°C
Degree of protection according to IEC 60529:	IP20
Area of application:	For indoor use only
Maximum altitude:	2000 m

## 10.3 Dimensions

All figures show the Hexapod in the reference position. Dimensions in mm. Note that the decimal places are separated by a comma in the drawings.

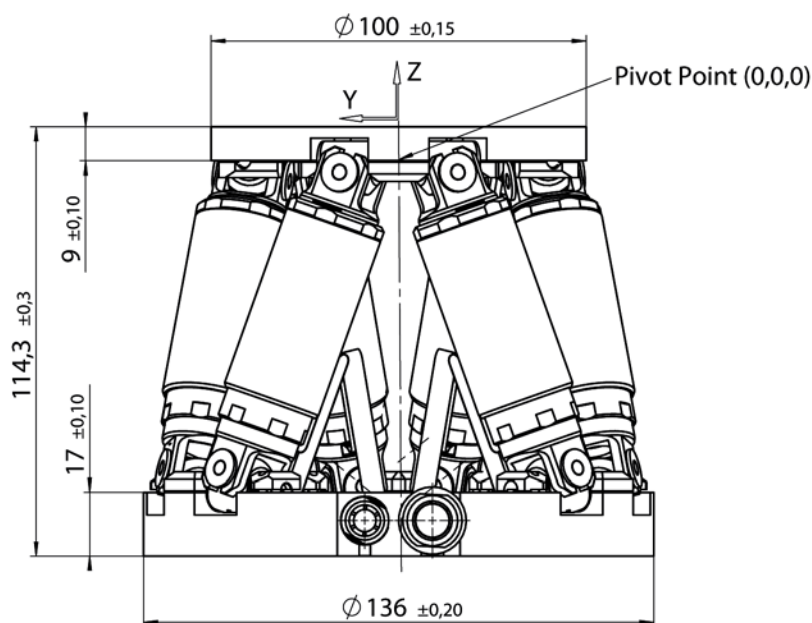


Figure 16: H-811 Hexapod front view (dimensions in mm)

The (0,0,0) coordinates refer to the origin of the XYZ coordinate system. When the default settings of the Hexapod controller are used, the origin of the XYZ coordinate system in the reference position corresponds to the pivot point.

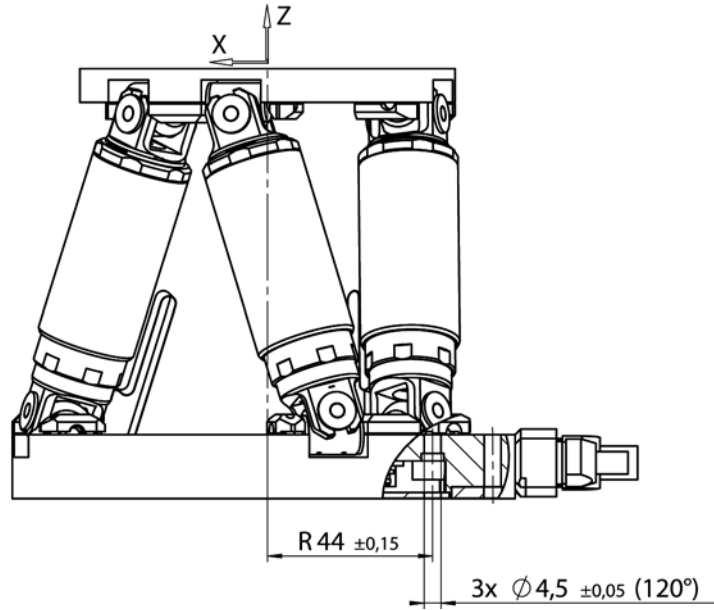


Figure 17: H-811 Hexapod side view (dimensions in mm)

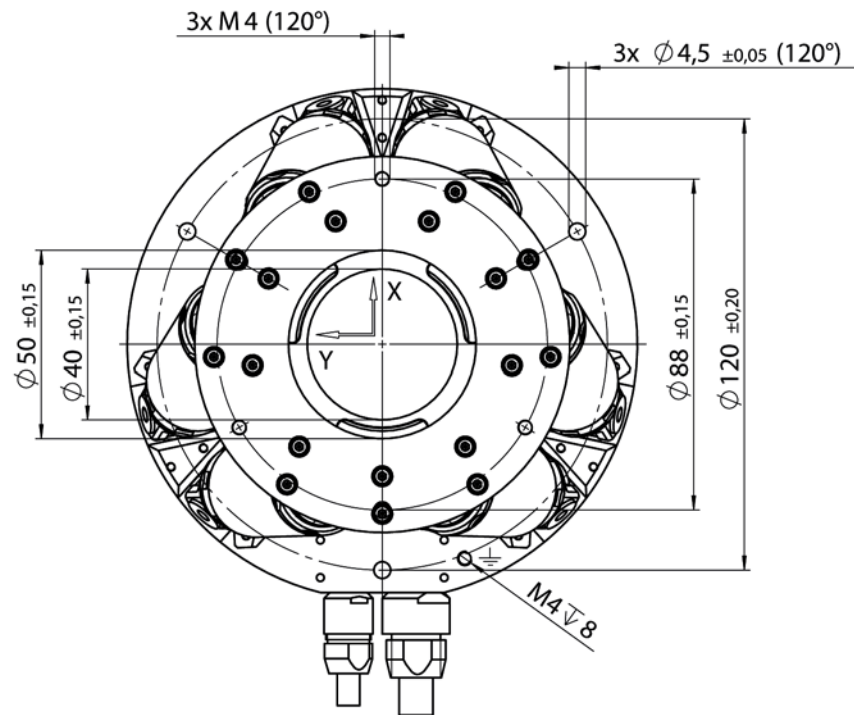


Figure 18: H-811 Hexapod top view (dimensions in mm)

**INFORMATION**

Only three of the six mounting holes in the base plate are visible in the figure.  
 Dimensions and position of the non-visible mounting holes:  
 3x  $\varnothing 4.5 \pm 0.05$  ( $120^\circ$ ) on a circle with  $\varnothing 88 \pm 0.15$  mm; arrangement on the circle corresponds to the positions of the three visible mounting holes.  
 All six mounting holes are visible in the figure in "Mounting the Hexapod on a Surface" (p. 26).

## 10.4 Pin Assignment

### 10.4.1 Power Source Connection

**Not** for the vacuum version:  
 power supply of the motors via 4-pin, A-coded M12 connector


Pin	Function	
1	GND	
2	GND	
3	24 V DC	
4	24 V DC	

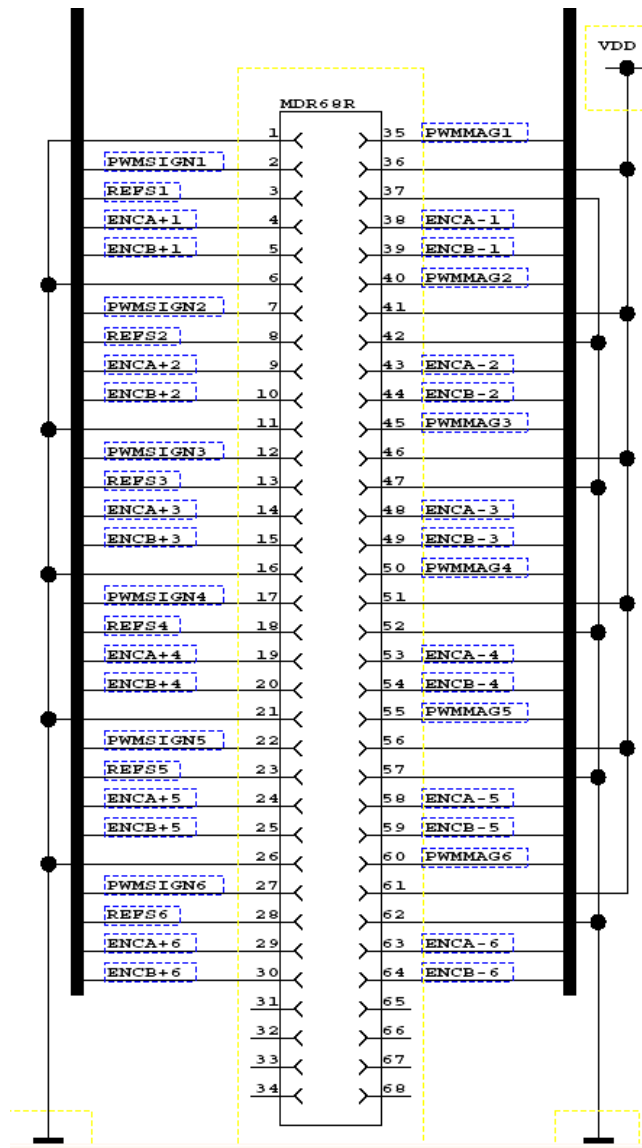
**Only** for the vacuum version:  
 power supply via 2-pin LEMO connector, type FFA.1S.302.CLLC52

Pin	Function	
1 (female)	GND	
2 (male)	24 V DC	

### 10.4.2 Data Transmission Connection

Not for the vacuum version:  
 data transmission between the H-811 and Hexapod controller via MDR68 connector

Function	Connector
All signals: TTL	



**Only** for the vacuum version:  
 data transmission between the H-811 and Hexapod controller, connection of the Hexapod to the vacuum feedthrough via HD Sub-D 78 connector, male (Positronic)

Function	Connector
All signals: TTL	

Pins that are not listed in the following table are not connected.

Pin	Function
1	GND
2	PWMSign1
3	Refs1
4	ENCA+1
5	ENCB+1
6	GND
7	PWMSign2
8	Refs2
9	ENCA+2
10	ENCB+2
11	GND
12	PWMSign3
13	Refs3
14	ENCA+3
15	ENCB+3
40	GND
41	PWMSign4
42	Refs4
43	ENCA+4

Pin	Function
21	PWMMag1
22	VDD
23	GND
24	ENCA-1
25	ENCB-1
26	PWMMag2
27	VDD
28	GND
29	ENCA-2
30	ENCB-2
31	PWMMag3
32	VDD
33	GND
34	ENCA-3
35	ENCB-3
60	PWMMag4
61	VDD
62	GND
63	ENCA-4



Pin	Function
44	ENCB+4
45	GND
46	PWMSign5
47	Refs5
48	ENCA+5
49	ENCB+5
50	GND
51	PWMSign6
52	Refs6
53	ENCA+6
54	ENCB+6

Pin	Function
64	ENCB-4
65	PWMMag5
66	VDD
67	GND
68	ENCA-5
69	ENCB-5
70	PWMMag6
71	VDD
72	GND
73	ENCA-6
74	ENCB-6



## 11 Old Equipment Disposal

In accordance with the applicable EU law, electrical and electronic equipment may not be disposed of with unsorted municipal wastes in the member states of the EU.

When disposing of your old equipment, observe the international, national and local rules and regulations.

To meet the manufacturer's product responsibility with regard to this product, Physik Instrumente (PI) GmbH & Co. KG ensures environmentally correct disposal of old PI equipment that was first put into circulation after 13 August 2005, free of charge.

If you have old PI equipment, you can send it postage-free to the following address:

Physik Instrumente (PI) GmbH & Co. KG  
Auf der Römerstr. 1  
D-76228 Karlsruhe, Germany





## 12 Glossary

### Work space

The entirety of all combinations of translations and rotations that the Hexapod can approach from the current position is referred to as the work space.

The work space can be limited by the following external factors:

- Installation space
- Dimensions and position of the load

### Pivot point

The pivot point describes the center of rotation (intersection of the rotational axes U, V and W). When the standard settings for the pivot point coordinates are used, the pivot point is located at the origin of the XYZ coordinate system after a reference move, see the dimensional drawing (p. 48) for more information.

The pivot point is shifted along with the platform during translations. Rotations do not change the position of the pivot point. The pivot point coordinates remain unchanged in both cases.

The pivot point coordinates can be changed in the Hexapod controller.

### XYZ coordinate system

The position and orientation of the Cartesian XYZ coordinate system cannot be changed, which is why the system is referred to as spatially fixed. The axes X, Y and Z are referred to as translational axes.

The intersection of the axes of the spatially-fixed Cartesian XYZ coordinate system (0,0,0) is referred to as the origin.

The Z axis is always perpendicular to the base plate of the Hexapod.

The following example figures of the H-810 Hexapod show that the XYZ coordinate system does not move along with motions of the platform.

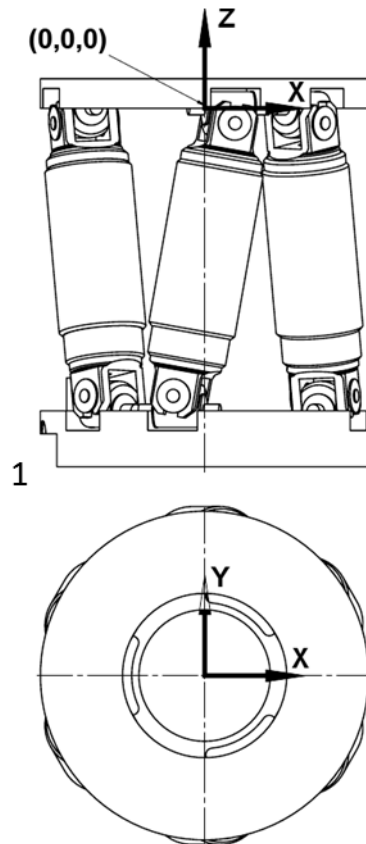


Figure 19: H-810 Hexapod in the reference position.

1 Cable outlet

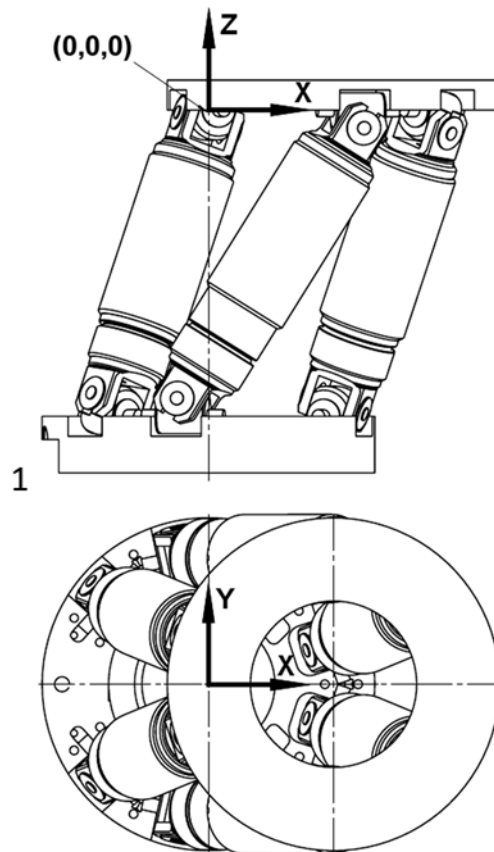


Figure 20: H-810 Hexapod, the platform of which has been moved in X.

1 Cable outlet





## 13 Appendix

### In this Chapter

Explanations of the Performance Test Sheet.....	61
EC Declaration of Conformity.....	62

### 13.1 Explanations of the Performance Test Sheet

The Hexapod is tested for the positioning accuracy of the translational axes before delivery. The performance test sheet is included in the scope of delivery.

The following figure shows the test setup used.

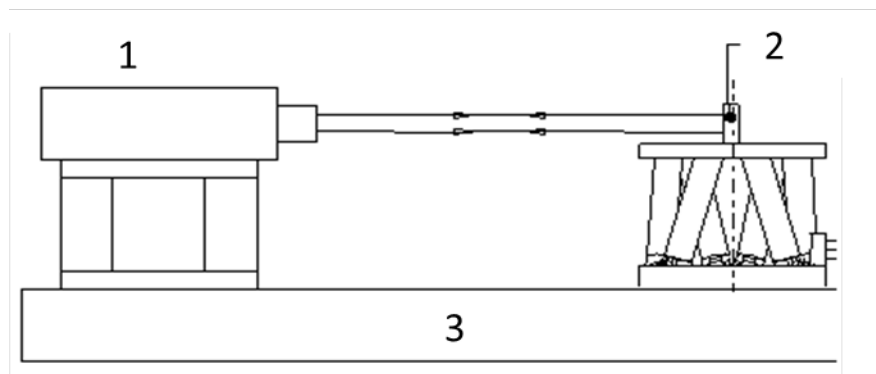


Figure 21: Test setup for measuring the X or Y axis.

- 1 Laser interferometer
- 2 Mirror
- 3 Bench

The following test cycles are performed:

- Movement over the entire travel range with at least 20 measuring points, in at least five cycles.
- Movement over partial sections, e. g.  $\pm 1$  mm in increments of e. g. 10  $\mu\text{m}$

## 13.2 EC Declaration of Conformity



### Declaration of Conformity

according to DIN EN ISO/IEC 17050-1

**Manufacturer:** Physik Instrumente (PI)  
GmbH & Co. KG

**Manufacturer's Address:** Auf der Roemerstraße 1  
D-76228 Karlsruhe,  
Germany



**The manufacturer hereby declares that the product**

**Product Name:** Miniature-Hexapod Microrobot, Direct Drive

**Model Numbers:** H-811

**Product Options:** all

complies with all relevant provisions of the **Machinery Directive (2006/42/EC)**.  
Furthermore, it complies with all provisions of the **EMC Directive (2004/108/EC)**.

**The applied standards certifying the conformity are listed below.**

**Safety of Machinery:** EN 12100-1: 2011-03, EN-12100-2: 2011-03

**Electromagnetic Emission:** EN 61000-6-3: 2007-09, EN 55011: 2009

**Electromagnetic Immunity:** EN 61000-6-1: 2007-10

The person authorized to compile the technical file is: Dr. Christian Rudolf  
Address: see manufacturer's address

March 02, 2012  
Karlsruhe, Germany

  
Dr. Karl Spanner  
President

Physik Instrumente (PI) GmbH & Co. KG, Auf der Roemerstraße 1, 76228 Karlsruhe, Germany  
Phone +49 721 4846-0, Fax +49 721 4846-1019, E-mail info@pi.ws, www.pi.ws

PIEZO NANO POSITIONING

