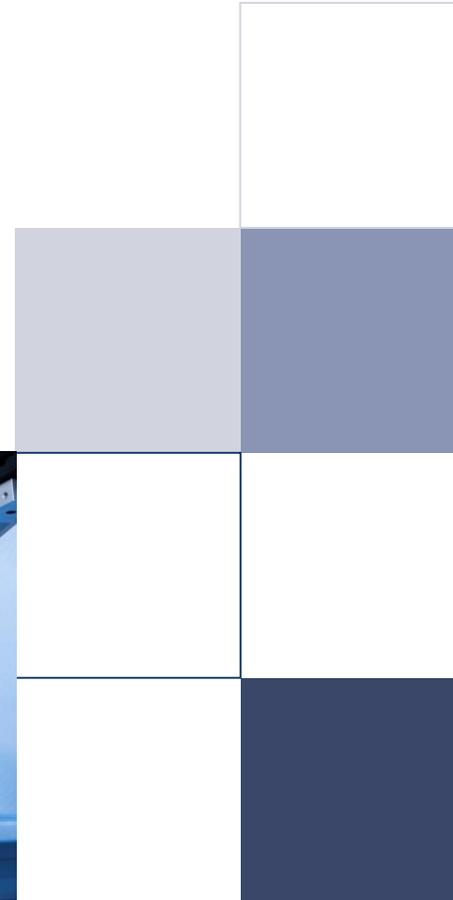
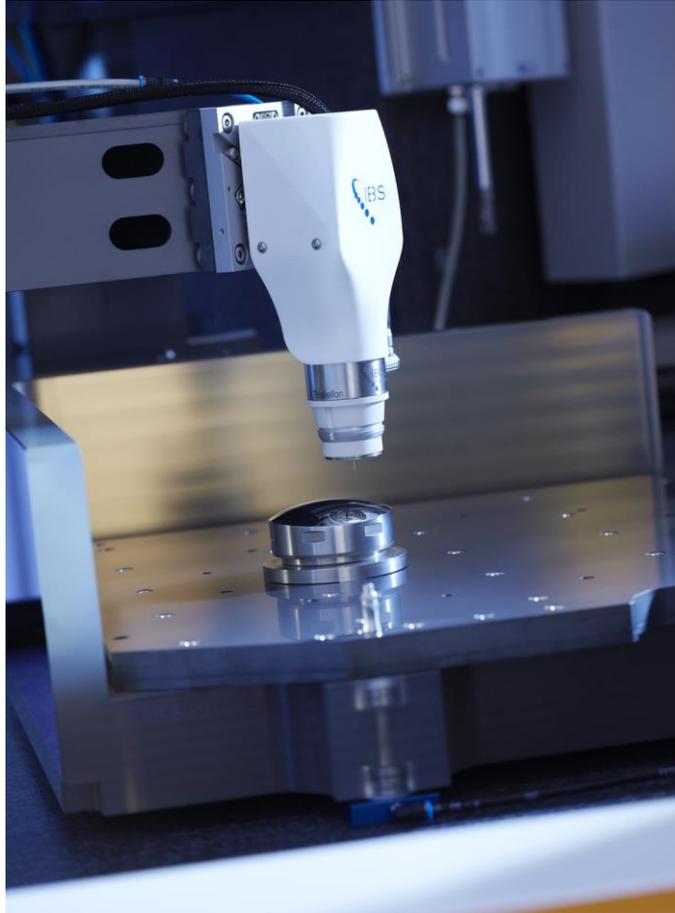


Dr Theresa Spaan-Burke
1st Dec 2020



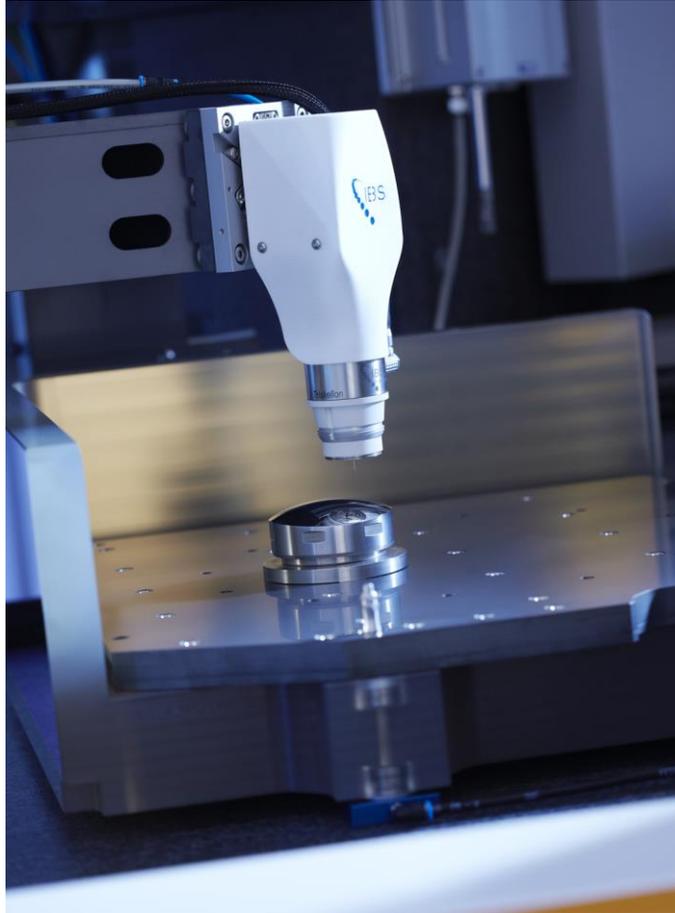
High precision in reel-to-reel printed flexible electronics
Special VDMA Productronics Online-Seminar

Solutions Where Ultra-Precision Engineering is Required

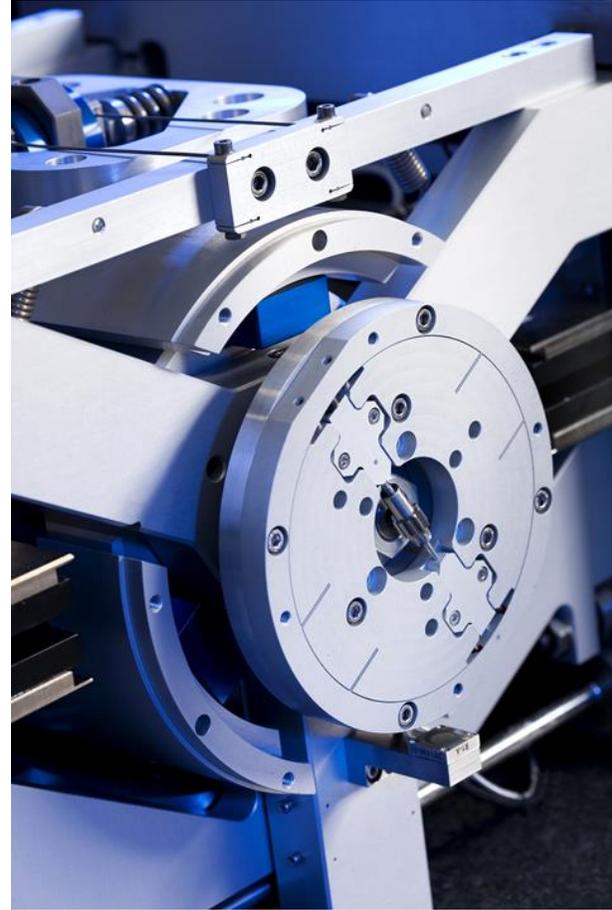


Ultra Precision Measurement

Solutions Where Ultra-Precision Engineering is Required

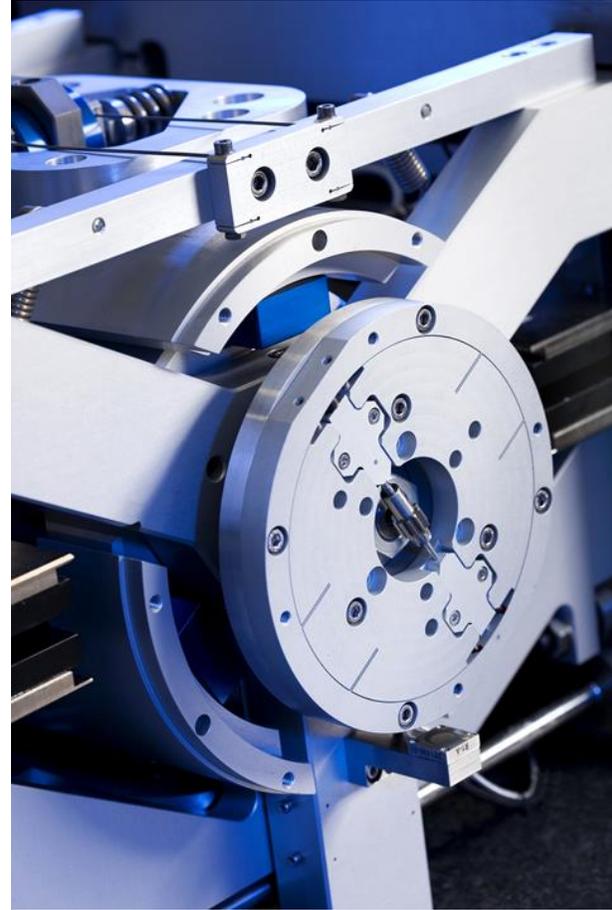
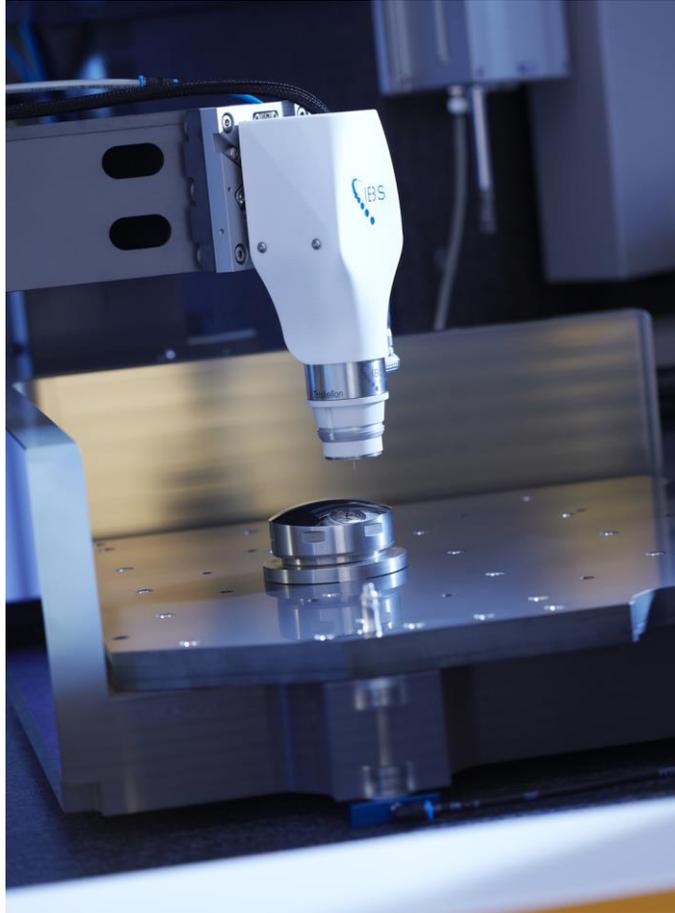


Ultra Precision Measurement



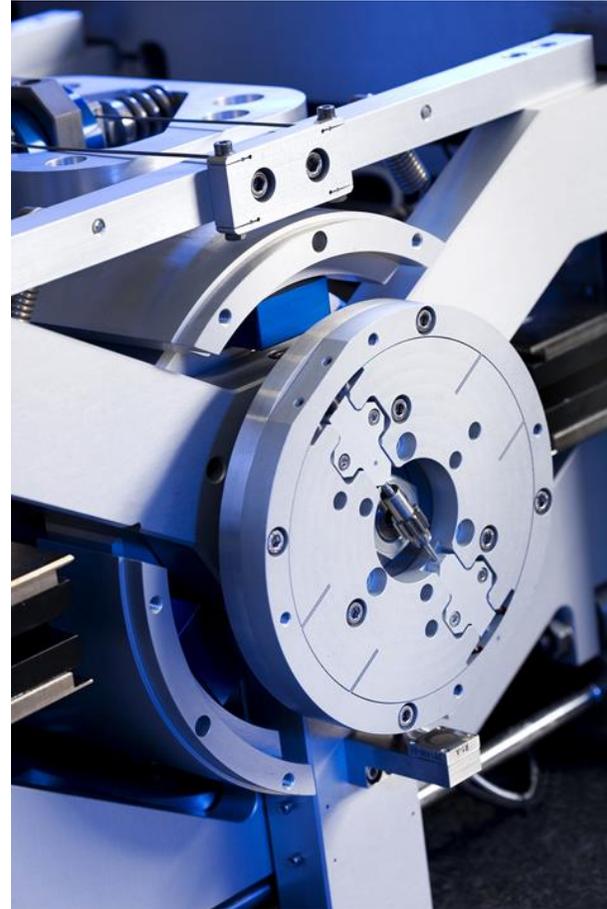
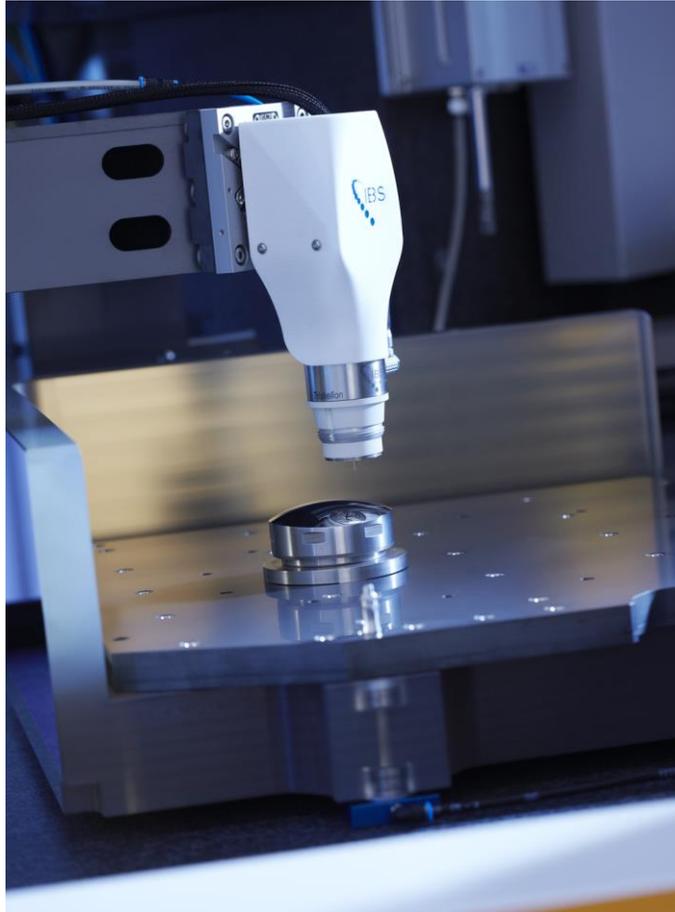
Ultra Precision Engineering

Solutions Where Ultra-Precision Engineering is Required



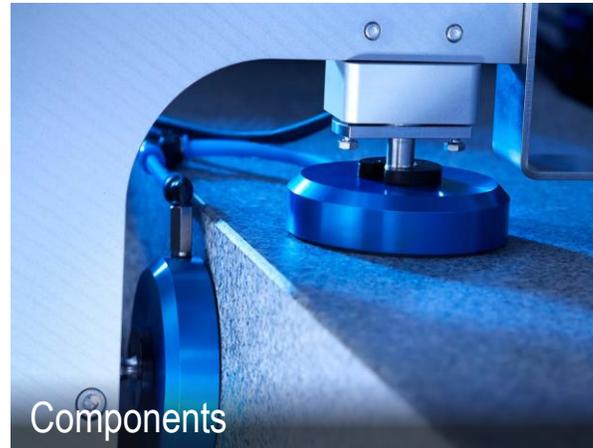
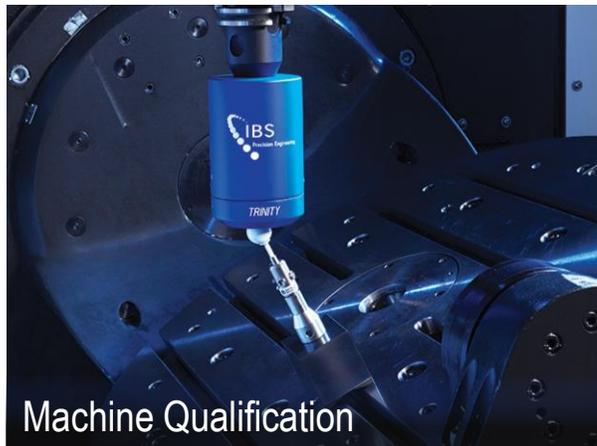
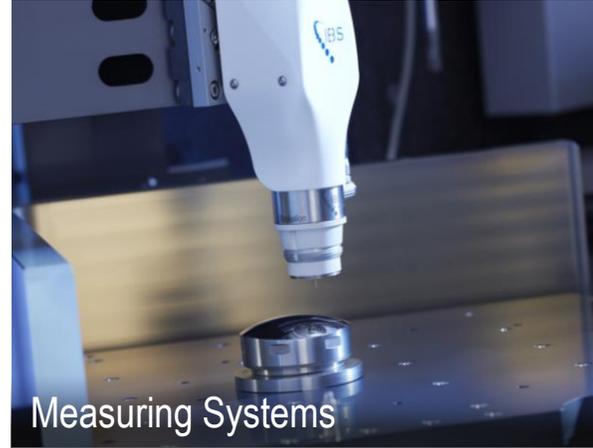
Everything we do is based on our unique metrology expertise

Solutions Where Ultra-Precision Engineering is Required

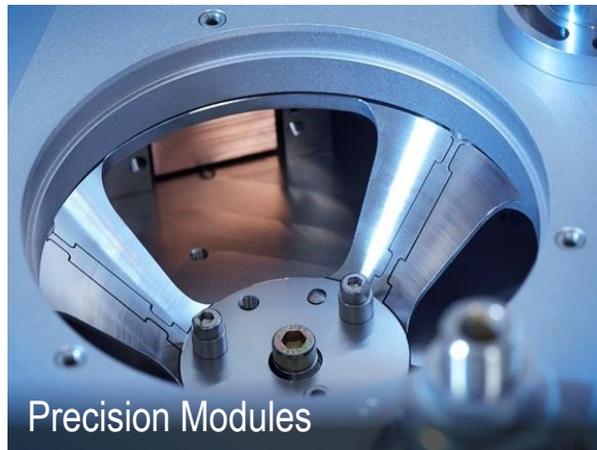


Serving high-tech manufacturing sector, scientific instrument makers
and research institutes for over 25 years

Product Groups



Product Group



Engineering Solutions

In-Line Interferometry for R2R Production

ARINNA – **A**Real **I**nterferometer for **N**anoscale Surfaces:

- Nanometer accuracy
- High speed measurement (~1s)
- Stepped structures
- Designed for in-line capability

Application challenge: In-line measurement of OPV scribes.

- Real-time data to R2R laser scribe process
- Low reflectivity OPV



ARINNA interferometer

In-Line Interferometry for R2R Production

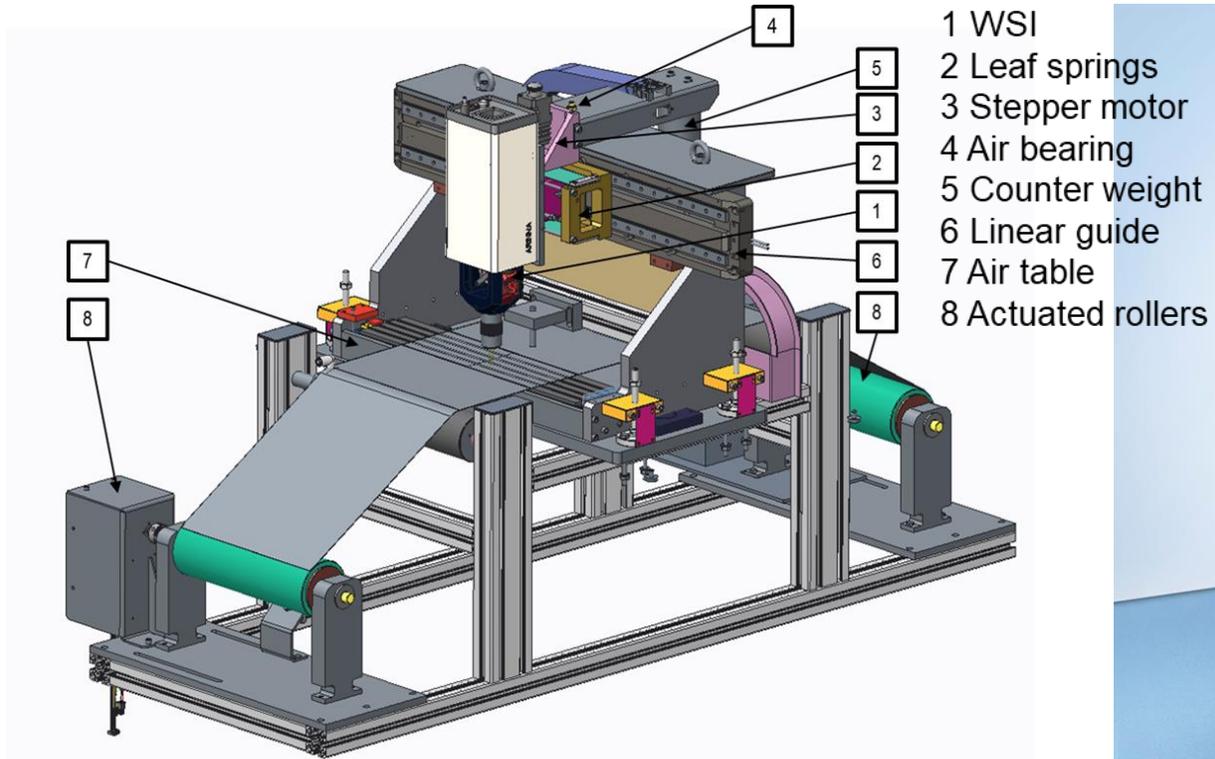
ARINNA – **A**Real **I**nterferometer for **N**anoscale Surfaces:

- Step 1 – OPV measurement
 - Demonstrate ability to measure on static samples
- Step 2 – R2R measurement
 - Web stabilisation (x-, y-, z-)



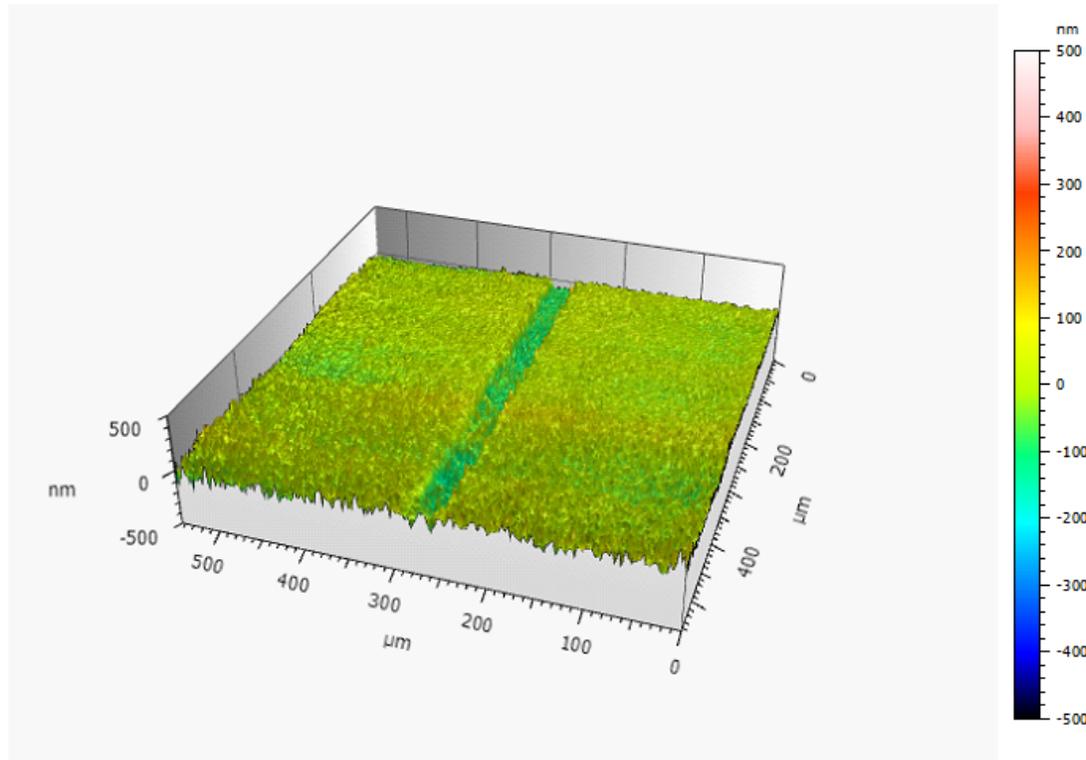
ARINNA interferometer

Stationary laser scribe measurement OPV

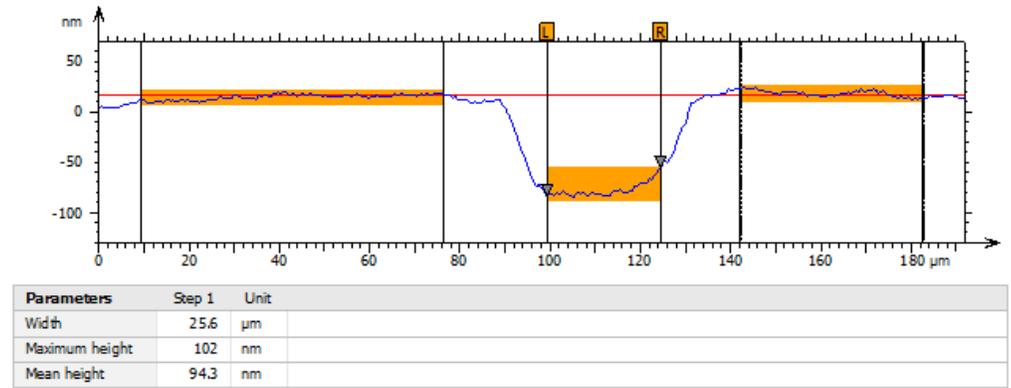


Laser scribe measurement OPV

- PET/ITO with laser scribes

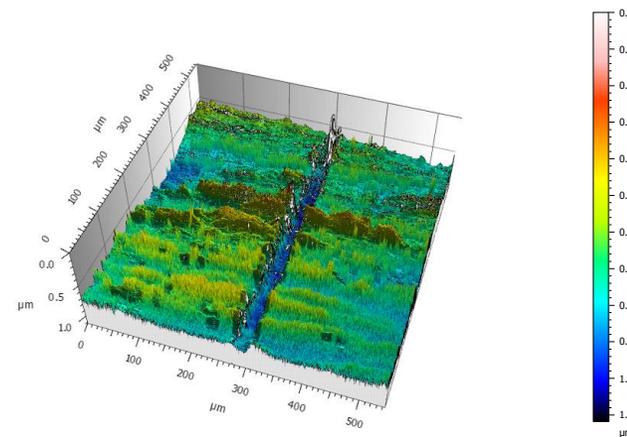
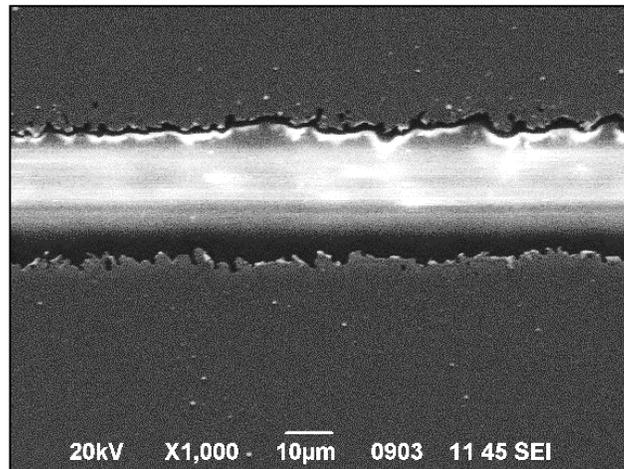


- Width = 25.6 μm
- Mean depth = 94.3 nm



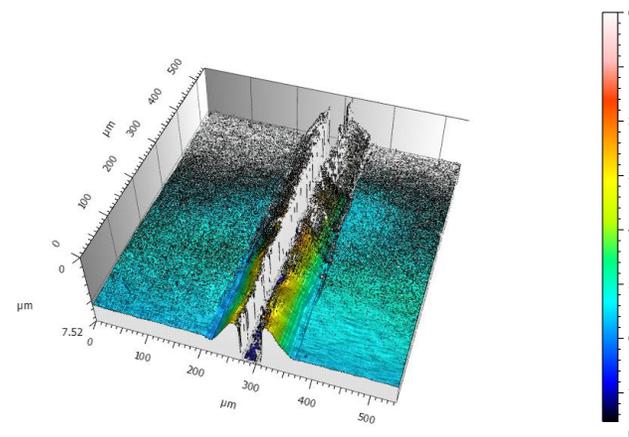
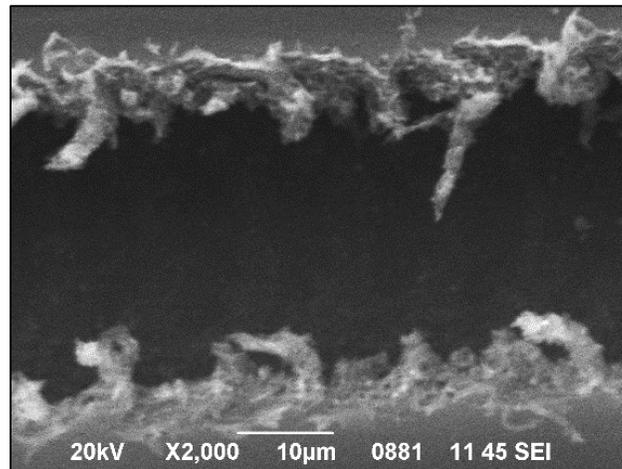
Laser scribe measurements at different stages

- P1 scribe



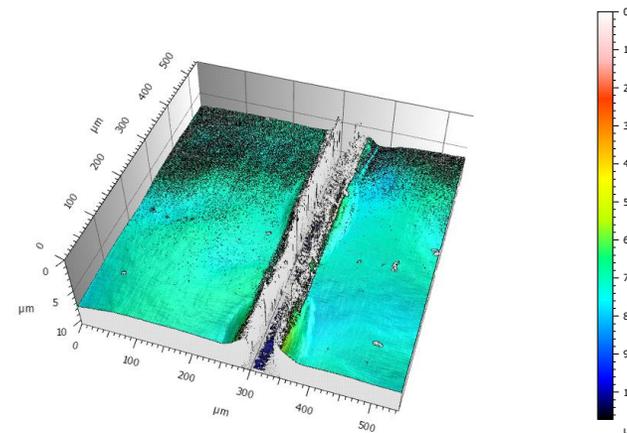
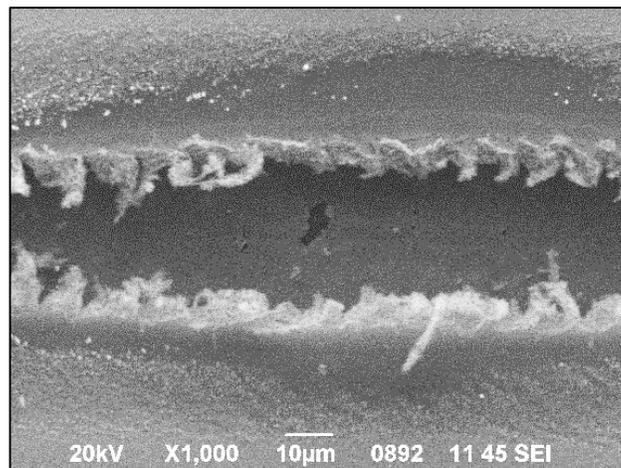
Laser scribe measurements at different stages

- P2 scribe



Laser scribe measurements at different stages

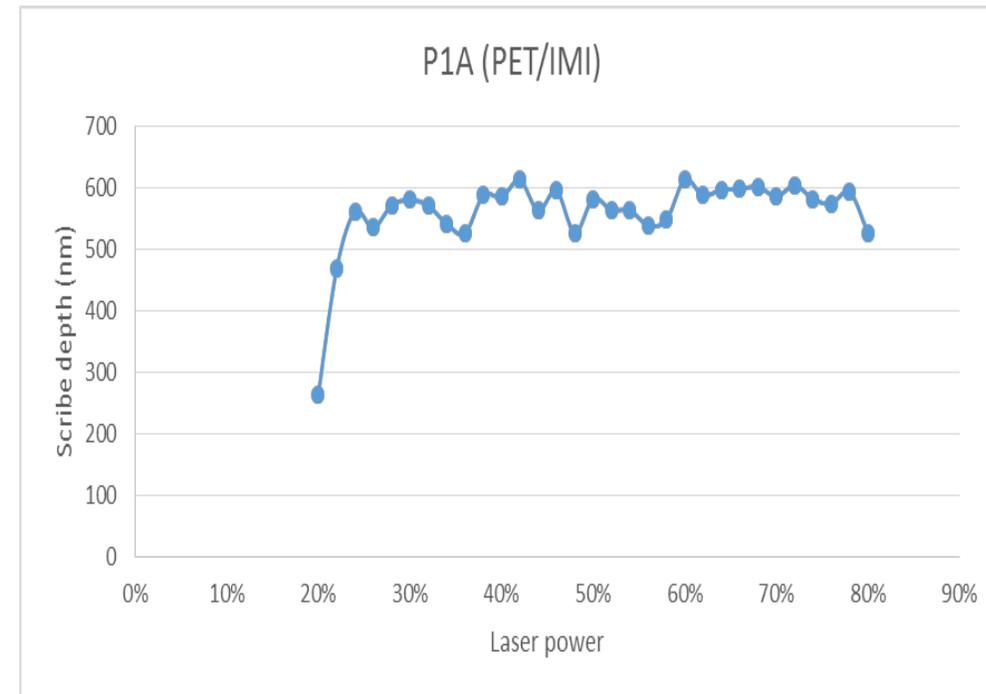
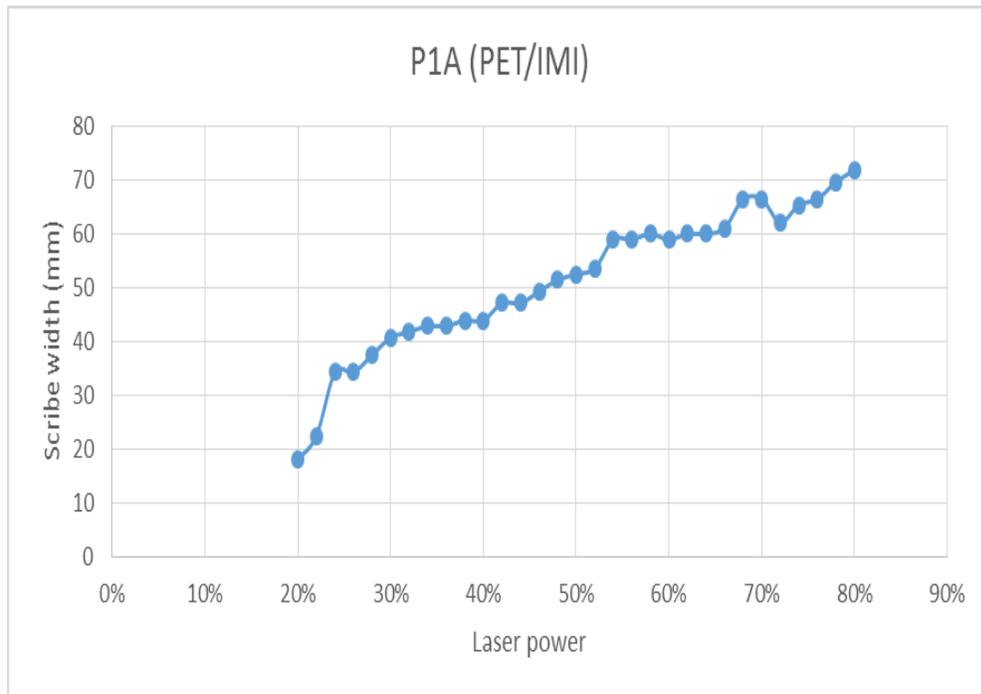
- P3 scribe



Scribe width and depth versus laser power

- P1A, PET/IMI

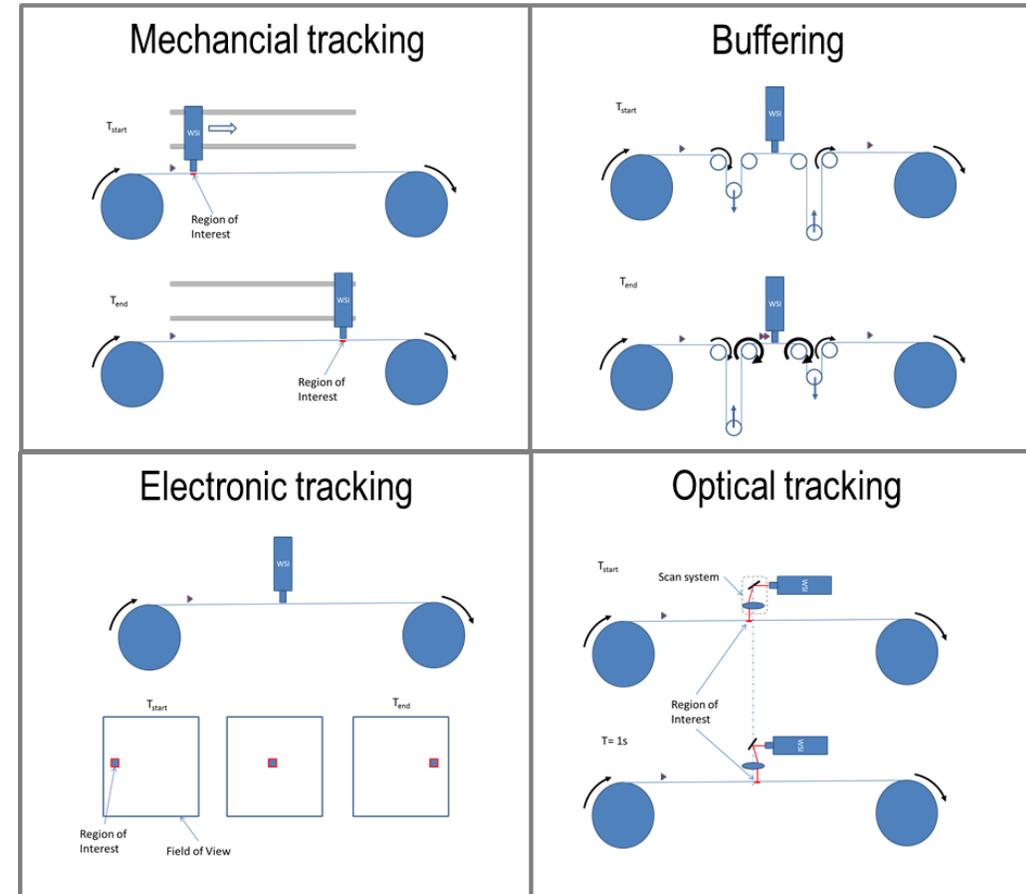
- Width increases with laser power
- For laser power > 24 %, depth constant



In-line scribe measurement

Challenges for in-line characterisation of OPV scribes with depths from $1\mu\text{m}$ to 100nm :

- Vertical web stability ($\sim 1\mu\text{m}$)
- Moving web (up to $5\text{m}/\text{min}$)
- Limited integration space



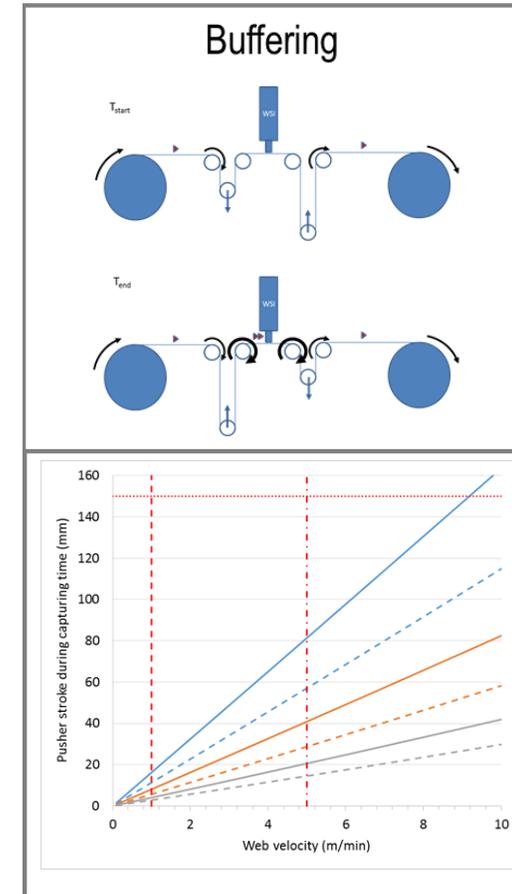
In-line scribe measurement

Challenges for in-line characterisation of OPV scribes with depths from $1\mu\text{m}$ to 100nm :

- Vertical web stability ($\sim 1\mu\text{m}$)
- Moving web (up to $5\text{m}/\text{min}$)
- Limited integration space

Buffering option chosen:

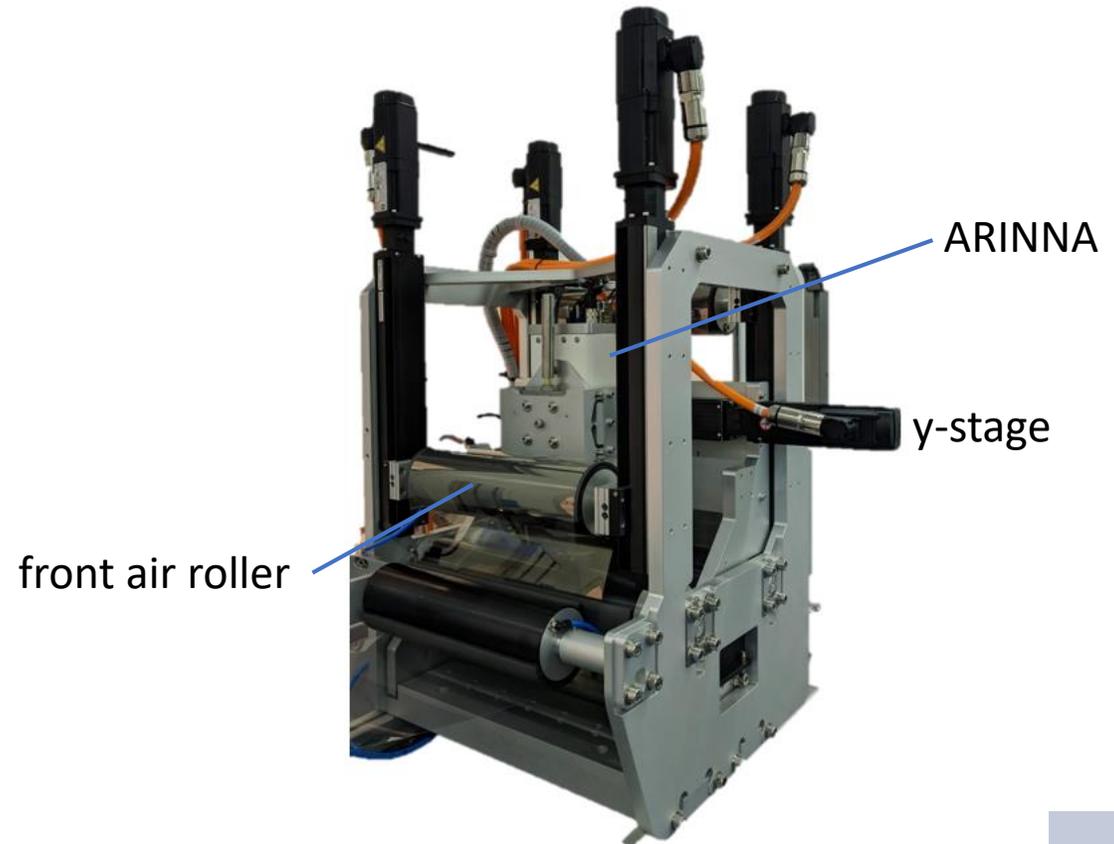
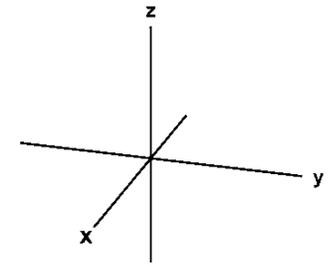
- Avoids head acceleration
- Speeds up to $5\text{m}/\text{min}$ possible in given space



Integrated dancer

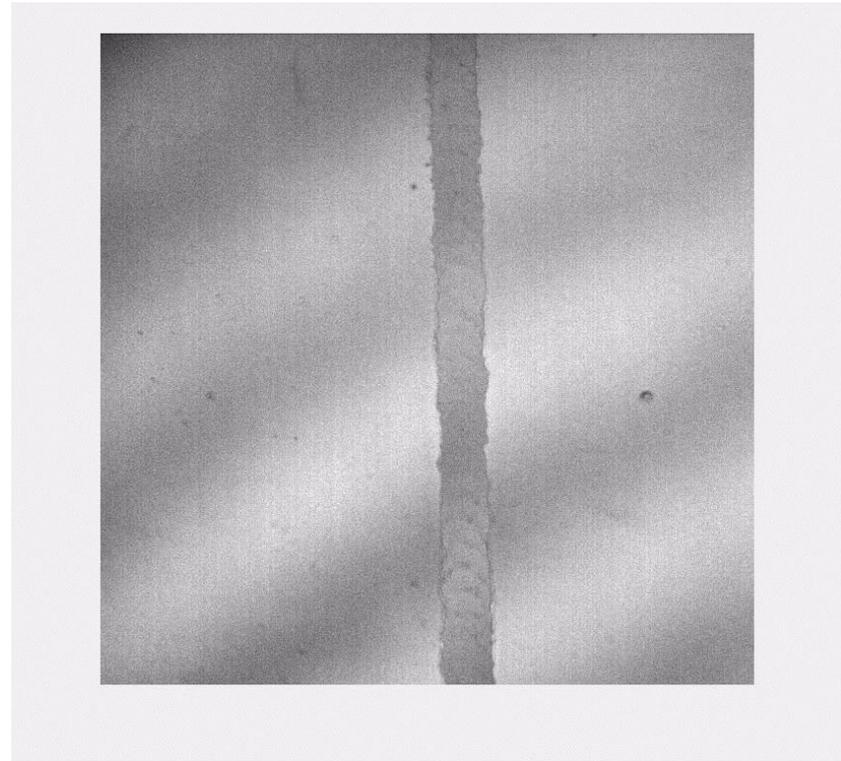
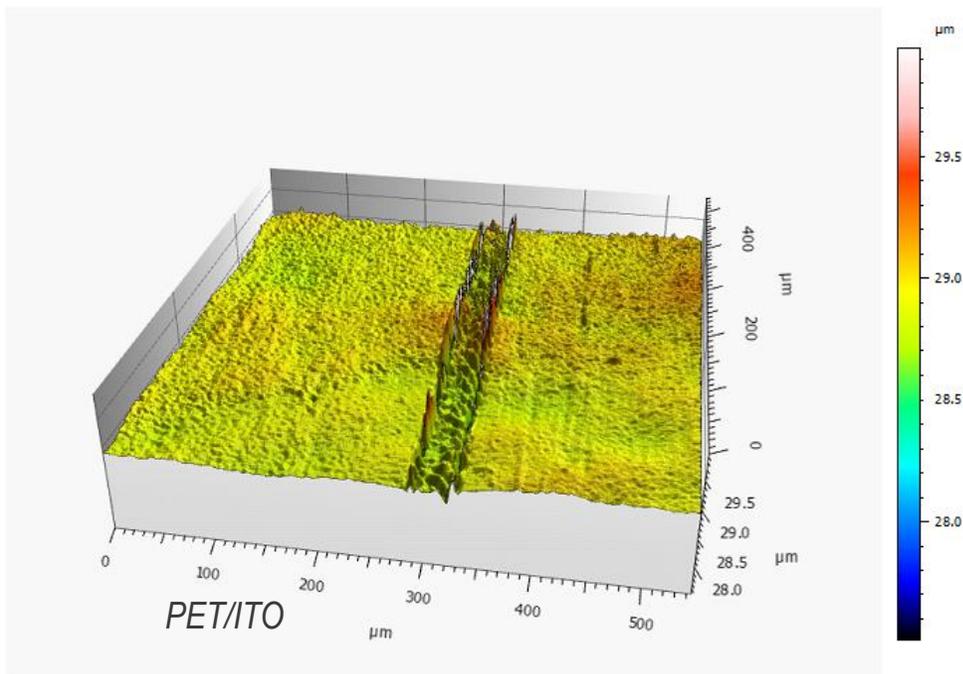
Dancer solution developed to buffer foils up to 10m/min:

- y-stage for head positioning across the web
- z-stage autofocusing
- 2 off air rollers provide dance



In-line scribe measurement

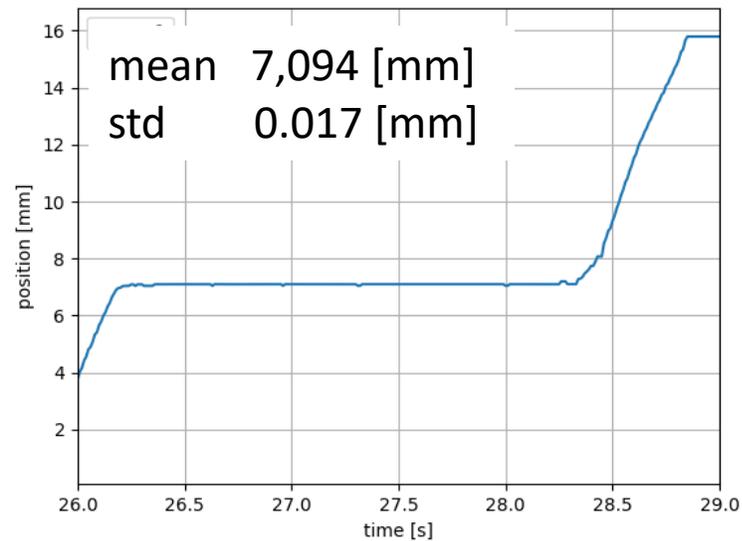
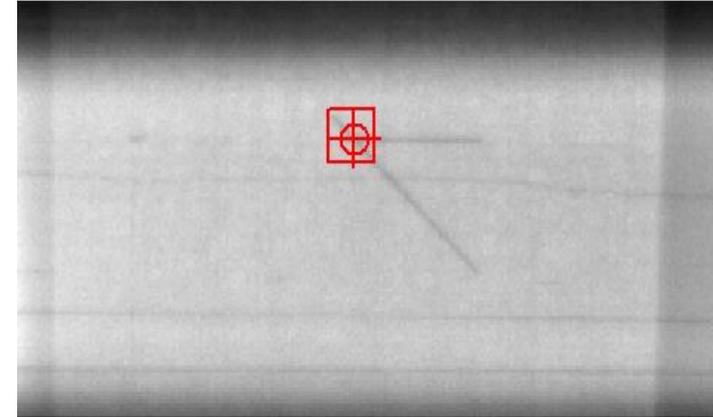
- Width = 29.4 μm
- Mean depth = 93.7 nm, maximum depth 114 nm
- Web travel 336 μm during measurement



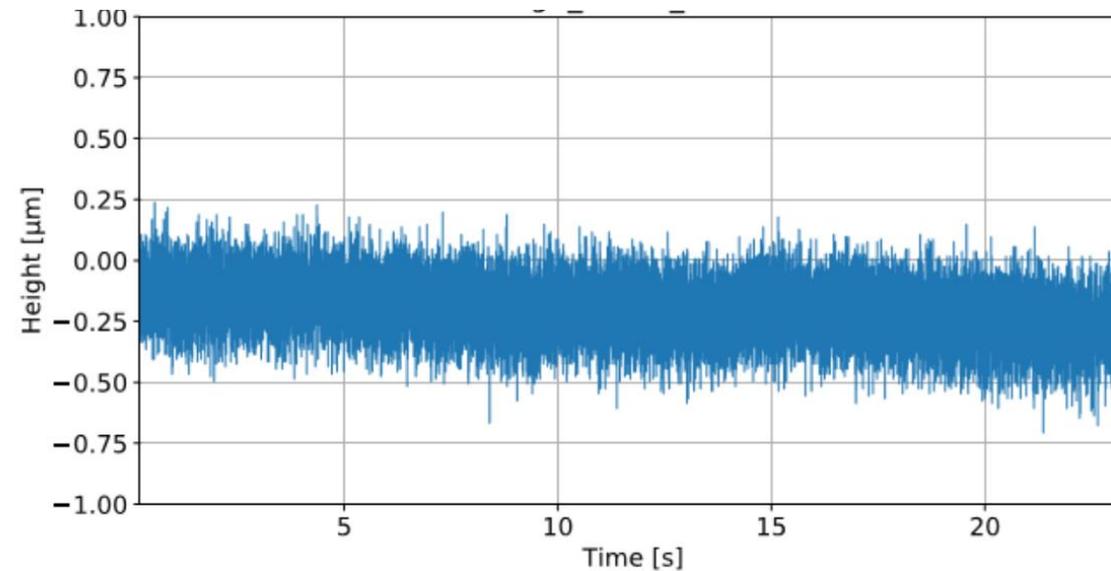
Improved dancer

To improve dancer performance:

- Marker detection triggers dancer
- $<1 \mu\text{m}$ web z-stabilization by means of vacuum/air table

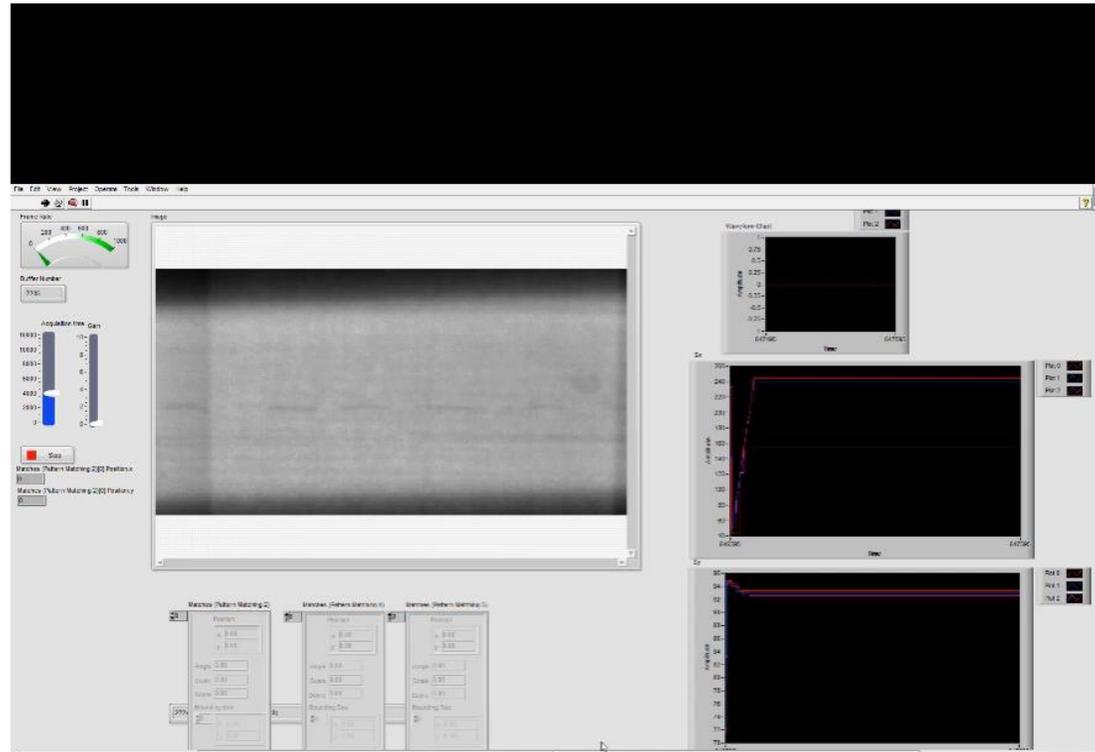


x position held



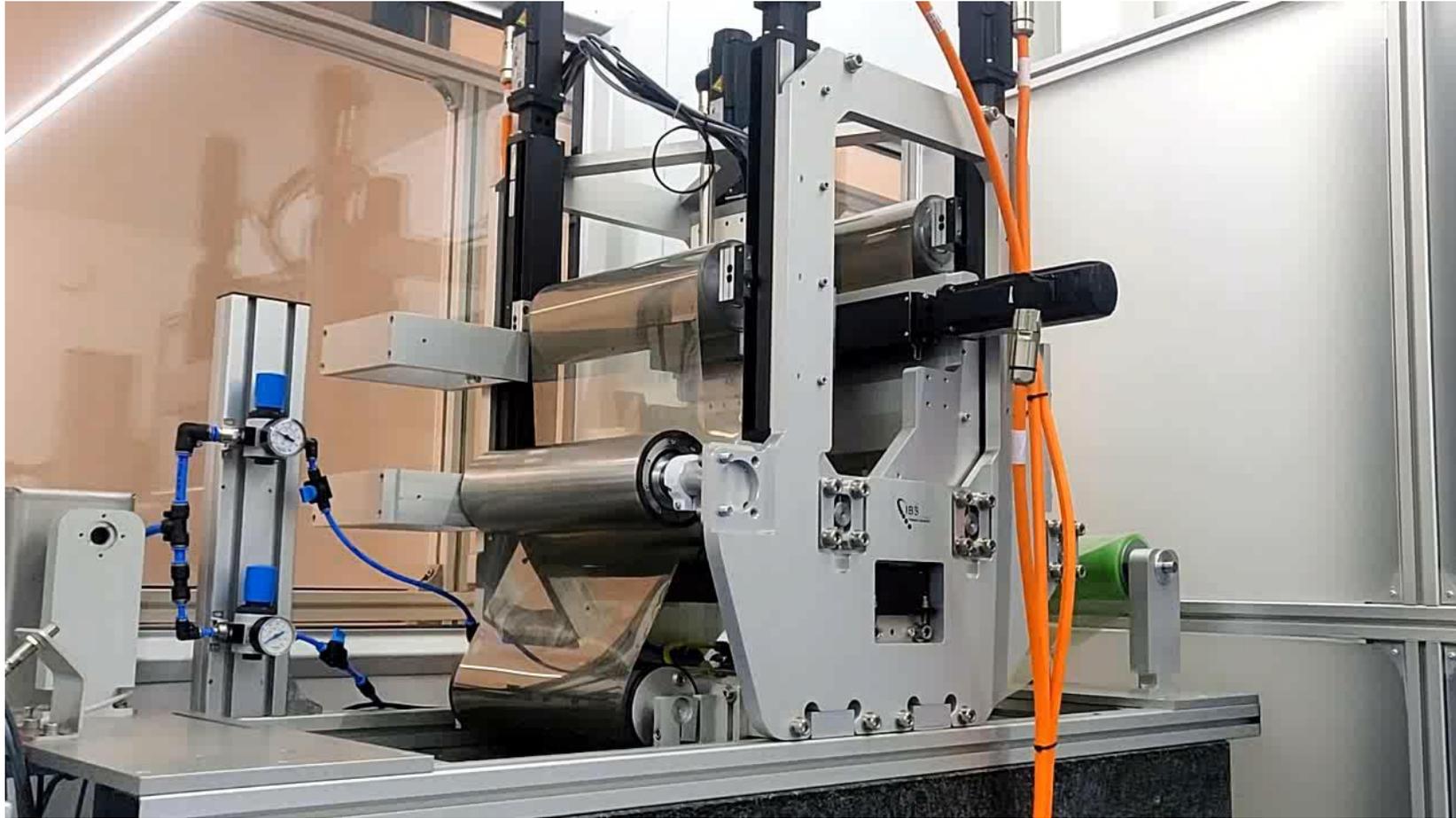
z-stability

Improved dancer - marker detection



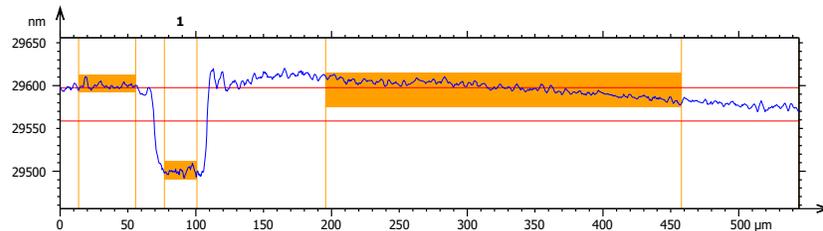
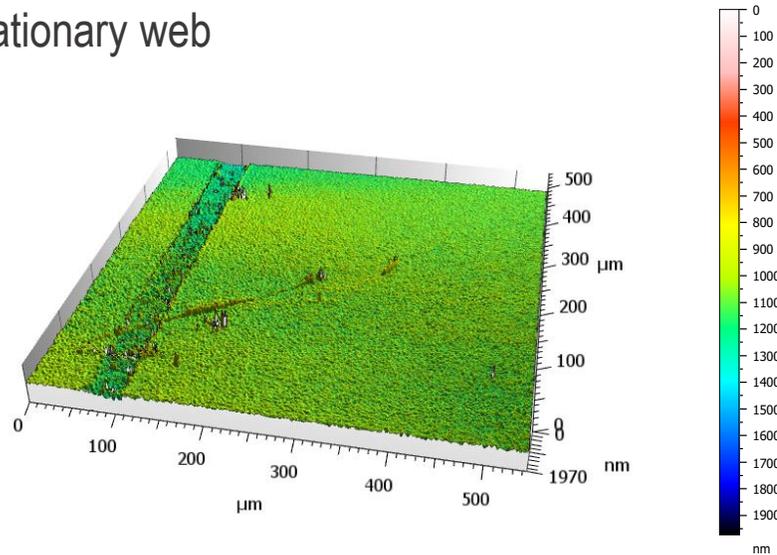
Marker found by camera

Integrated dancer system



First successful height maps with dancer

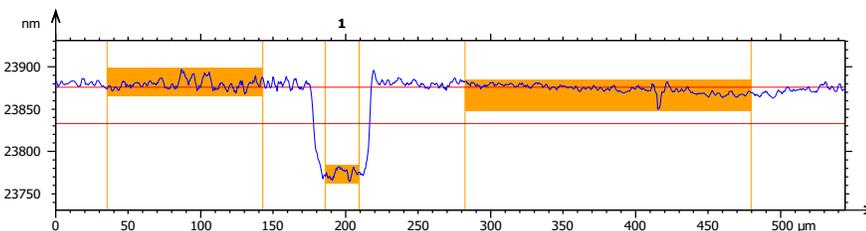
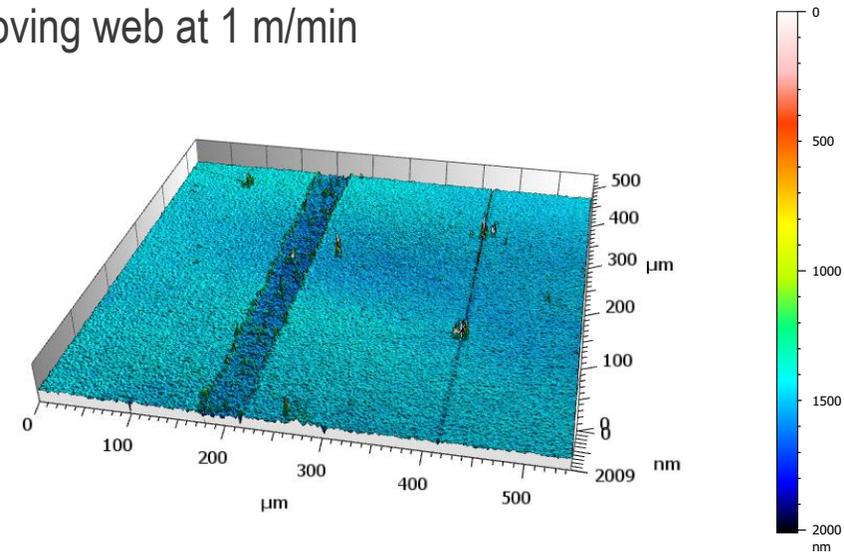
Stationary web



Parameters	Step 1	Unit
Width	23.98	μm
Mean depth	97.82	nm

- Width = 24 μm
- Depth = 98 nm

Moving web at 1 m/min

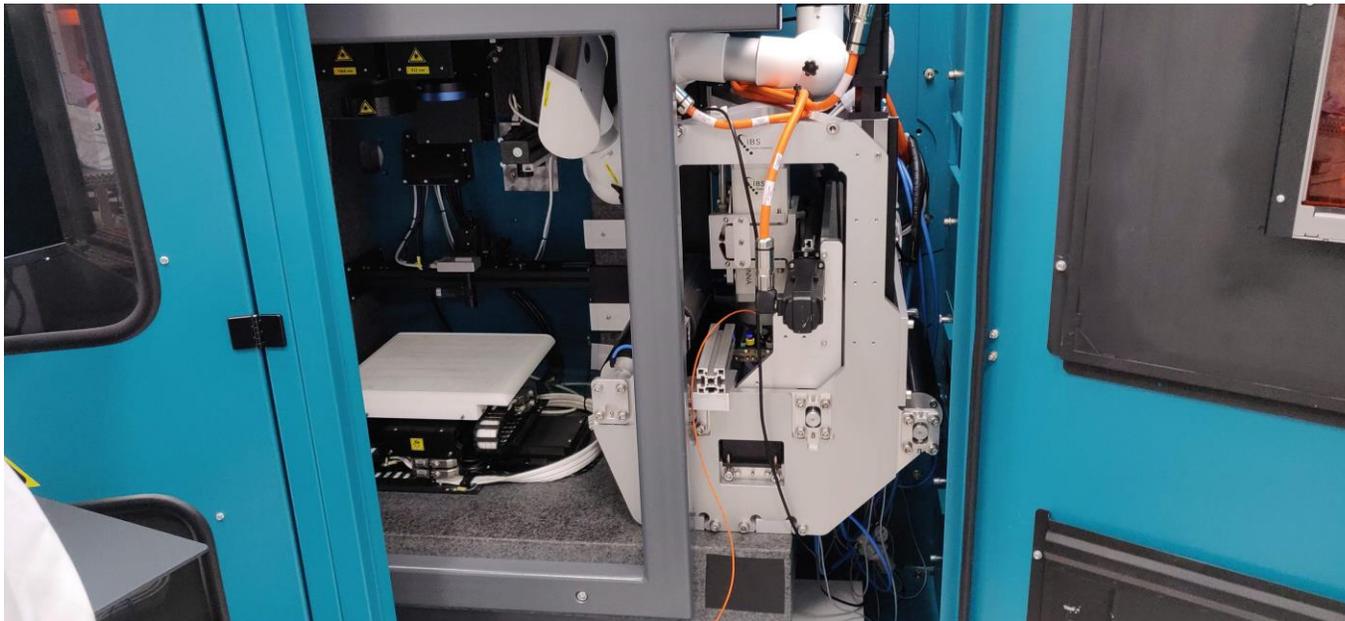


Parameters	Step 1	Unit
Width	23.44	μm
Mean depth	101.4	nm

- Width = 23 μm
- Depth = 101 nm

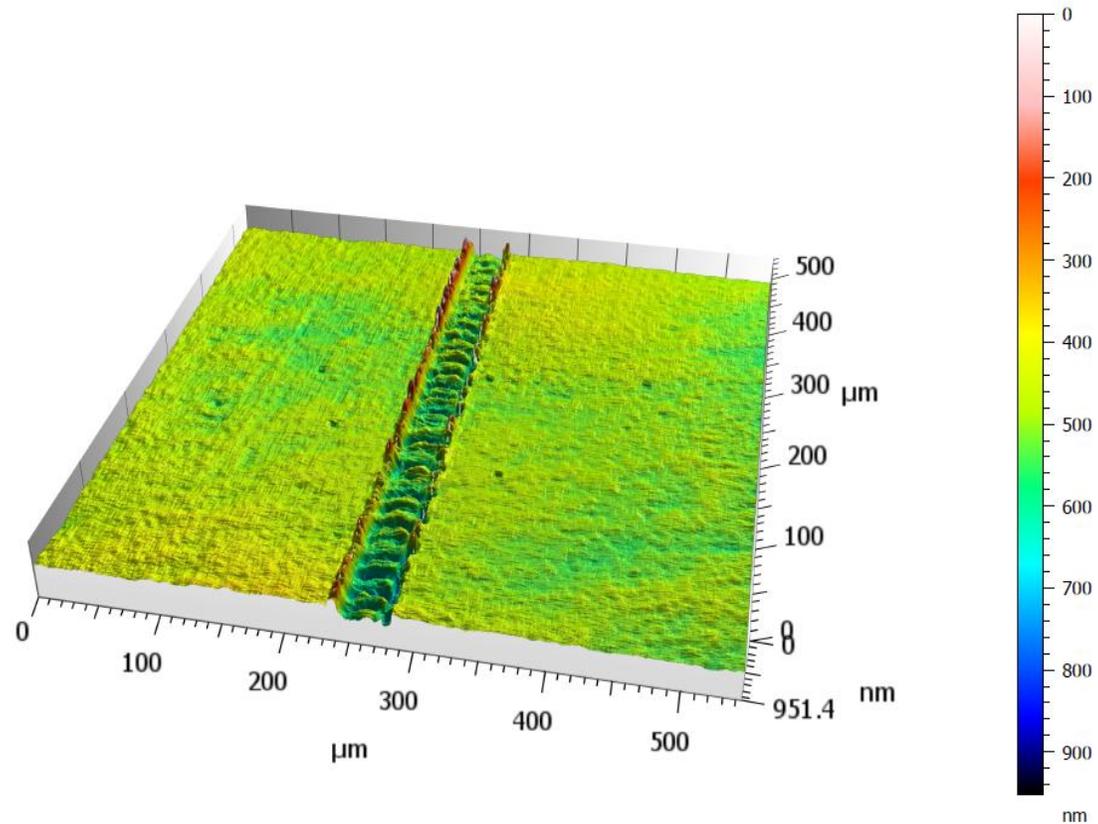
Integrated Dancer

- The system, including dancer, has been integrated at the Centre for Nanotechnology, AuTH, Greece.



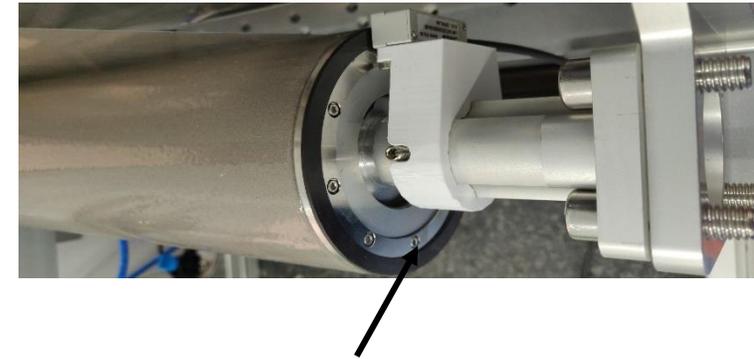
Pilot line measurement with dancer 1m/min

- PET/IMI

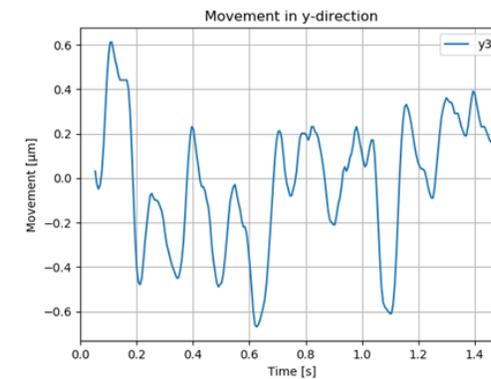
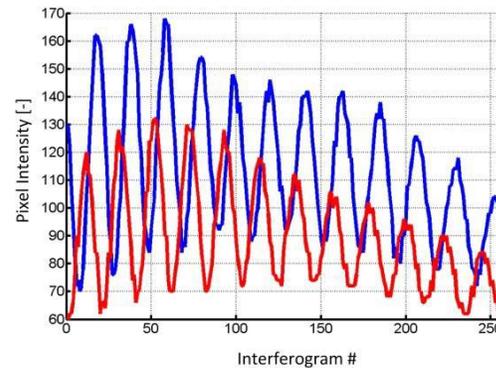
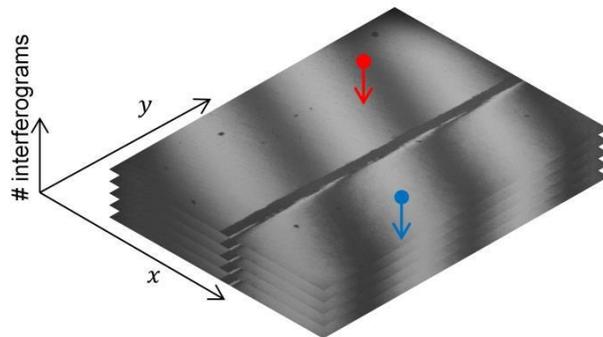


Improved dancer - encoder

- Encoder positioned at the first roller in the dancer system
- Object tracking software enables tracking of web (scribe) during individual scan.
- $<1\mu\text{m}$ motion in x- and y- achieved.

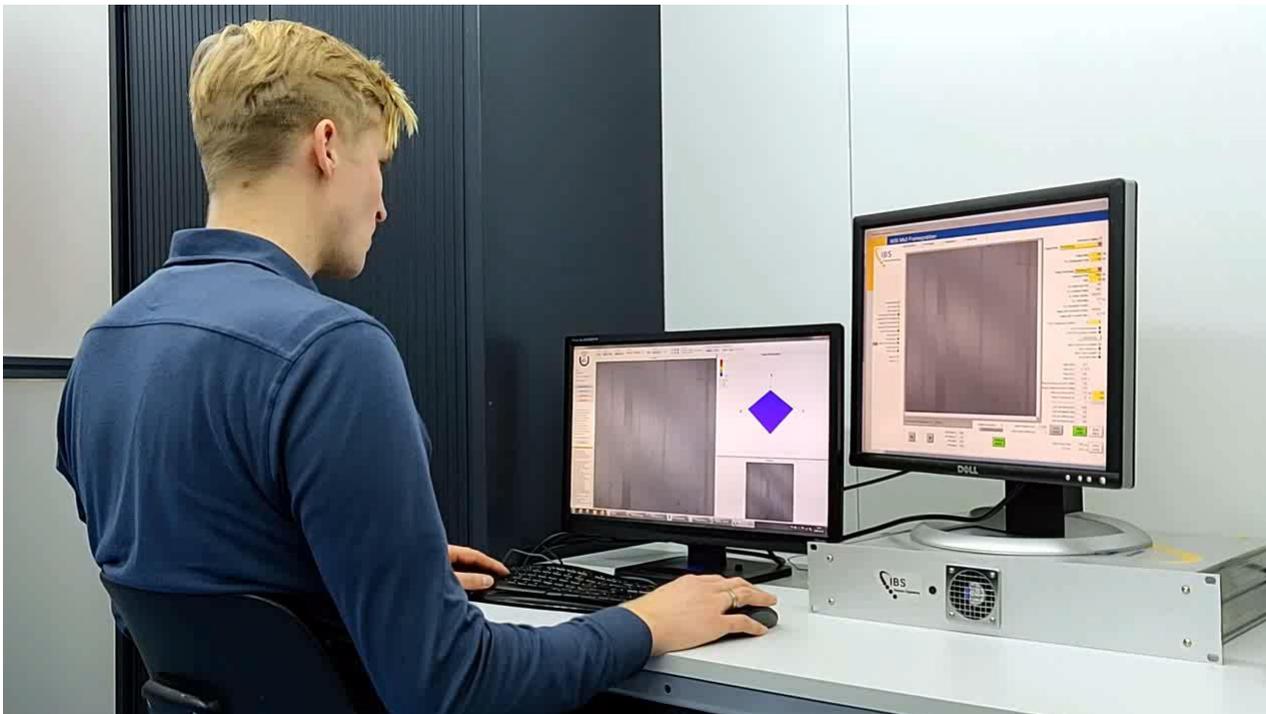


Encoder at the first roller



In-line measurement automation

- Automatic measurement at predefined interval
- Automatic feature extraction (depth and width)
- Trend graph of data
- Validity check against predefined range
- TCP/IP communication of depth and width to client



Scribe measurement

Enable feature detection

Template Name: Smartline_laser_scribe_full3.mnt

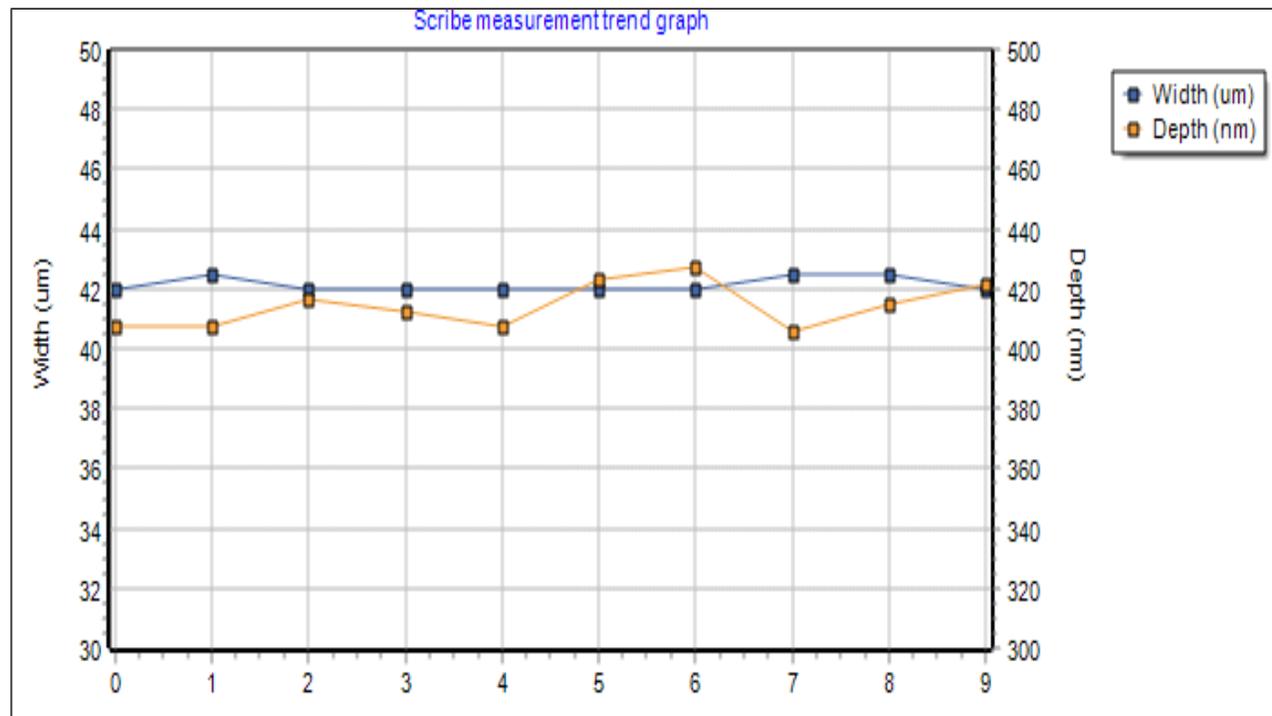
Control

Measure every Seconds

Send every measurement to clients @ port:3025

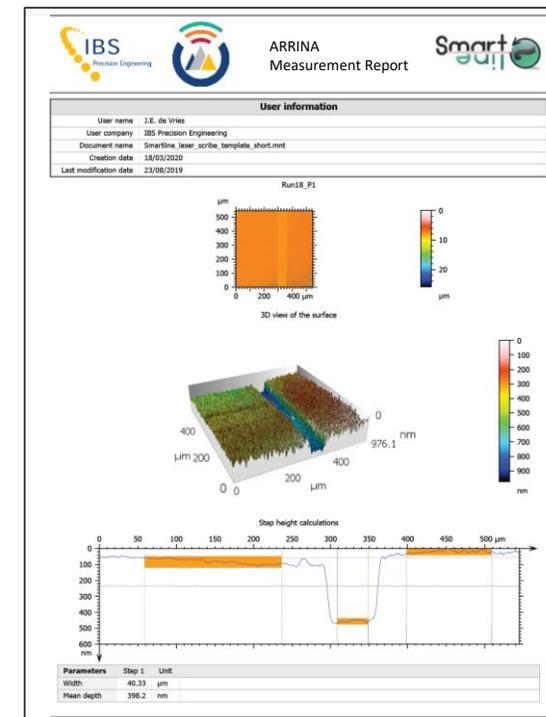
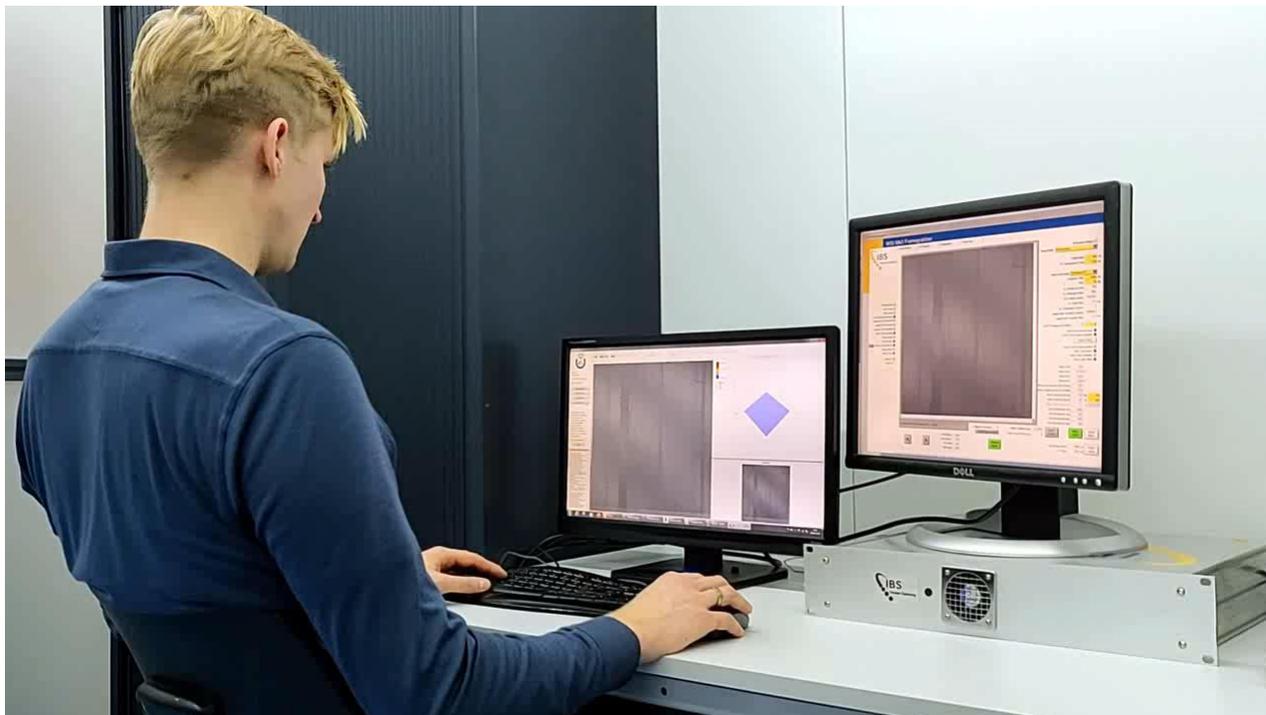
In-line measurement automation

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In-line measurement automation

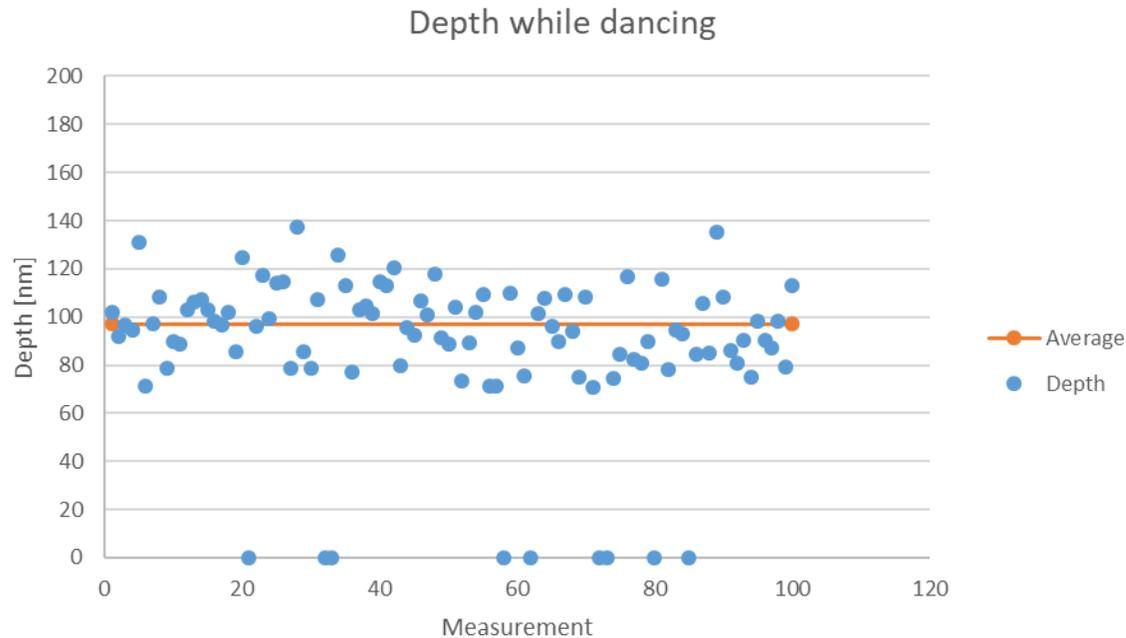
- Automatic measurement at predefined interval
- Automatic feature extraction (depth and width)
- Trend graph of data
- Validity check against predefined range
- TCP/IP communication of depth and width to client
- Measurement report in PDF of last measurement



100 measurements in-line 1m/min

- 100nm (nominal) scribe
- At IBS due to Corona
- Stddev static measurements 9.5nm

Average	96.96 nm
Stddev	15.30 nm
Standard error of the mean	1.92 nm
Confidence interval	3.84 nm
Tolerance range	50-150 nm



100 measurements in-line 1m/min

- At 1m/min 9 out of 10 measurements were found to be within the 95% confidence level



- 1m/min



- 2m/min

Summary

- Successful first measurement of laser scribes on OPV;
- Automated in-line measurements at a predefined location;
- Automated feature extraction - scribe width and depth;
- Check of the laser scribe width and depth against predefined acceptance values;
- Display of series of measurements on a trend graph;
- Communication of measurement results to client server for production optimisation

Acknowledgements:

IBS Colleagues: Jorrit de Vries, Rens van der Nolle, Behrooz Daneshkhah, Mario Felius, Peter Overshie

AuTH: Printed material and SEM images.

We would like to acknowledge funding received from the European Union's Horizon 2020 research and innovation programme as part of the project SmartLine (www.smartline-project.eu).



Thanks for your attention
Time to start the dialogue

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