

**System for generating the movement of a support plate in six
degrees of freedom**

This invention relates to a system for generating movement of a support plate in several degrees of freedom.

5 This system has for purpose to allow for the relative movement between two plates, a support plate (or platform) which is able to carry an optical, mechanical or other device, in order to take measurements, processing, etc., and a lower plate which is placed on a support element, for example on a workstation.

10 In order to generate such a movement in the six degrees of freedom possible, a positioner of the hexapod type is known, which is a parallel robot constituted of six actuators forming legs. The six legs are actuated in order to change the length and vary the orientation of the upper platform. As such, a set of unique leg lengths is associated to a given position of the upper platform.

15 Systems of the parallel robot type, in particular hexapods, generally have disadvantages, and in particular a substantial encumbrance and/or a limited area of work.

Moreover, it is known through document FR – 2 757 925, a modular device for setting a charge into movement in at least three degrees of freedom, comprising a triangular platform supporting a load.

20 The purpose of the present invention is to overcome these disadvantages. It relates to a system for generating movement of a support plate, the support plate being, in a so-called neutral position, substantially parallel to an XY plane defined by a so-called X direction and a so-called Y direction, said system being configured to be able to move said plate in at least some of the six degrees of freedom, said six
25 degrees of freedom corresponding, respectively, to a so-called X_i translation along the X direction and a so-called θ_X rotation around this X direction, to a so-called Y_i translation along the Y direction and a so-

called θY rotation around this Y direction, to a so-called Z_i translation along a so-called Z direction and a so-called θZ rotation around this Z direction, with the Z direction being orthogonal to said X and Y directions.

According to the invention, said system for generating movement comprises at least two control stages superimposed in a direction Z and being secured to each other, at least one of said control stages comprises a control module, and said at least one control module comprises only movement units designed so as to each generate a translational movement in the XY plane, and this respectively in different directions.

As such, thanks to the invention, as specified below, the system for generating movement is of the modular type. Due to this modular architecture and the use of movement units designed to generate only translational movements, a very compact system for generating movement is obtained as specified hereinafter. In addition, the system for generating movement has an extended area of work. This makes it possible to overcome the aforementioned disadvantages.

Advantageously, the movement units are arranged in the XY plane and positioned in such a way as to have different directions of translation that form, respectively, an angle of 120° between them.

In a preferred embodiment, a first control module comprises:

- a first lower plate and a first upper plate;
- at least two movement units, the movement units being fixed on an upper face of the first lower plate; and
- straight guide rails, each one of said guide rails being mounted on one of said movement units to which it is associated, each one of said guide rails being arranged orthogonally to the direction of movement of the associated movement unit and being designed in such a way as to move under the action of the associated movement unit, each one of said guide rails carrying a mobile carriage which is designed

to be freely mobile orthogonally to the direction of movement of the associated movement unit, each one of said mobile carriages being connected to a lower face of the first upper plate.

In this case, in a first alternative embodiment, the first control module is designed to generate X_i and Y_i movements and it comprises two movement units and a straight auxiliary guide rail, the auxiliary guide rail being arranged in a direction different from the directions of movement of the two movement units and carrying a mobile carriage designed to be freely mobile, the mobile carriage being fixed to the lower face of the first upper plate.

Furthermore, in a second alternative embodiment, the first control module is designed to generate Y_i and θ_Z movements and it comprises two movement units and a straight auxiliary guide rail, the auxiliary guide rail being arranged in a direction different from the directions of movement of the two movement units and carrying a mobile carriage designed to be freely mobile, each one of said mobile carriages being provided with a rotation system designed to rotate freely in the XY plane, the three rotation systems being connected, each one, to the lower face of the first upper plate. In this case, advantageously, the system comprises an auxiliary control stage designed to generate an X_i movement of the so-called first control module.

Moreover, in a third (preferred) alternative embodiment, the first control module is designed to generate X_i , Y_i and θ_Z movements, and it comprises:

- three movement units; and
- three straight guide rails, each one of said guide rails being mounted on one of said movement units to which it is associated, each one of said guide rails being arranged orthogonally to the direction of movement of the associated movement unit and being designed in such a way as to move under the action of the associated movement unit, each one of said guide rails carrying a mobile carriage which is designed

to be freely mobile orthogonally to the direction of movement of the associated movement unit, with each one of said mobile carriages being provided with a rotation system designed to be rotate freely in the XY plane, the three rotation systems being connected, each one, to the lower
 5 face of the first upper plate.

Moreover, in a preferred embodiment, a second control module is designed to generate θX , θY and Z_i movements, and it comprises:

- a second lower plate and a second upper plate;
- 10 - three movement units designed so as to generate a translational movement, the movement units being fixed on an upper face of the second lower plate; and
- three straight guide rails, each one of said guide rails being mounted, inclined in relation to the XY plane, on one of said
 15 movement units to which it is associated, each one of said guide rails being arranged longitudinally to the direction of movement of the associated movement unit and being designed in such a way as to move under the action of the associated movement unit, each one of said guide rails carrying a mobile carriage which is designed to be freely mobile, with
 20 each one of said mobile carriages being provided with a ball designed to be freely rotating, the three balls being articulated, each one, to the lower face of the first upper plate.

In a first alternative embodiment, it additionally comprises, at least one, but preferably several of the following three auxiliary control
 25 stages:

- an auxiliary control stage designed to generate an X_i movement;
- an auxiliary control stage designed to generate a Y_i movement; and
- 30 - an auxiliary control stage designed to generate a θZ movement.

Furthermore, in a second (preferred) alternative embodiment, the system for generating movement comprises only two control stages, of which a so-called first control stage comprises the so-called first control module designed to generate X_i , Y_i and θ_Z movements, and of which a so-called second control stage comprises said second control module designed to generate θ_X , θ_Y and Z_i movements.

The accompanying figures will show how the invention can be implemented. In these figures, identical references designate similar elements.

Figure 1 is a perspective view of a preferred embodiment of a system for generating movement.

Figure 2 is a perspective view, in a mounted position, of a first control module of the system for generating movement of figure 1, associated with an auxiliary control stage.

Figure 3 is a partially exploded perspective view of the control module of figure 2.

Figure 4 is a perspective exploded view of the control module of figure 2.

Figure 5 is a perspective view of a second control module of the system for generating movement of figure 1.

Figure 6 is a perspective exploded view of the control module of figure 5.

Figure 7 is a perspective view of the control module of figure 5, associated with two auxiliary control stages.

Figure 8 is a perspective view of the control module of figure 5, associated with three auxiliary control stages.

The system 1 shown in figure 1 and which illustrates the invention, is a system for generating a movement of a plate (or platform) 2, preferably globally flat, with respect to a support (not shown) whereon is placed (and in particular fixed) the system 1.

The plate 2, for example made of metal, is arranged substantially parallel to an XY plane defined by a so-called X direction (or longitudinal direction) and a so-called Y direction (or lateral direction), in a so-called neutral position of the plate 2, i.e. in a base position without
 5 activation of the various means of movement of the system 1 specified below.

These X and Y directions are part of a coordinate system R (or XYZ) which is shown in figures 1, 2 and 5 to 7. This coordinate system R intended to facilitate understanding comprises, in addition to
 10 the X and Y directions (or axes) forming the XY plane, a so-called Z direction (or axis) (or vertical) which is orthogonal to said XY plane.

For reasons of clarity, the coordinate system R shown in detail in figure 1 is positioned outside of the system 1. However, the Z direction passes through a central vertical axis.

15 As indicated hereinabove, the support plate 2 is in the neutral position (not activated), substantially parallel to the XY plane. The system 1 is designed to be able to move said plate 2 in at least some of the six degrees of freedom.

These six degrees of freedom (shown as double arrows)
 20 correspond, respectively, as shown in figure 1

- to a translation, named X_i , along the X direction;
- to a so-called θ_X rotation, around the X direction;
- to a translation, named Y_i , along the Y direction;
- to a so-called θ_Y rotation, around the Y direction;
- 25 - to a translation, named Z_i , along the Z direction; and
- to a so-called θ_Z rotation, around the Z direction.

The adjectives "upper" and "lower" in the description hereinafter apply in relation to the directions defined by the arrow of the Z direction, upper being in the direction (+z) of the arrow and lower being in
 30 the opposite direction (-z), as shown in figure 1.

The plate 2 can support particular elements (not shown), which can be fixed on it, via fastening means, for example screws, passing through the holes 3 that can be seen in the plate 2 (figure 1).

5 In addition, the system 1 can be placed and fixed on a support element (not shown) via fastening means, for example screws, passing through the holes 4 that can be seen in a lower plate 5 of the system 1 (figure 1).

10 In a preferred application, the system 1 is part of a precise positioning device (or machine) for the semiconductor industry, in particular for processing or control applications in a standard atmosphere or in empty tanks, or for the optical and optoelectronics industry, for the positioning of optics, optoelectronic components, etc.

15 In a preferred embodiment, shown in figure 1, the system 1 comprises two control stages E1 and E2 superimposed in a direction Z and being secured to each other.

The system 1 is of the modular type, and each one of said control stages E1 and E2 comprises a control module M1 and M2.

20 In addition, each one of said control modules M1 and M2 comprises movement units U1 and U2 designed to each generate only a translational movement in the XY plane.

25 These movement units U1 and U2 which each comprise for example an electric motor or a motor of another type, can be controlled, usually, by an operator (or by an automatic control system), by the intermediary of a control element not shown. In particular, the distance and the direction of translation (in the direction considered), and possibly the speed of translation, can be controlled. Each one of these movement units U1 and U2 therefore defines a motorised axis (according to its direction (or axis) of translation).

30 The sought position of the plate 2 is obtained by a particular combination of controls (and therefore of positioning) of the various movement units U1 and U2 considered.

In addition, the movement units U1 and U2 are designed to generate, each one, a translational movement, respectively in different directions. More precisely, the movement units U1 and U2 are arranged in the XY plane and positioned in such a way as to have different
 5 directions of translation that form, respectively, preferably an angle of 120° between them.

In the preferred embodiment, shown in figure 1, the system 1 comprises only the two control stages E1 and E2;

- of which the first lower control stage E1 comprises said
 10 control module M1, which is designed to generate X_i , Y_i and θ_Z movements (i.e. translations in the X and Y directions and a rotation around the direction Z); and

- of which the second upper control stage E2 comprises said control module M2, which is designed to generate θ_X , θ_Y and Z_i
 15 movements.

More precisely, in a preferred embodiment, the control module M1 comprises, as shown in figures 2 to 4:

- a lower plate 5 and an upper plate 6;
 - three movement units U1. The three movement units U1
 20 are fixed on an upper face 5A of the lower plate 5, as can be seen in figure 3; and
 - the straight guide rails 7.

Each one of the three guide rails 7 is mounted on one of the three movement units U1, to which it is associated.

25 As such, the control module M1 comprises one guide rail 7 per movement unit U1 and each movement unit U1 is provided with a guide rail 7.

Each one of the guide rails 7 is arranged orthogonally to the direction of movement of the associated movement unit U1, as shown for
 30 a guide rail 7 on the right portion of figure 3, which comprises a longitudinal axis L2. This longitudinal axis L2 of the guide rail 7 is

orthogonal to the longitudinal axis (or axis of movement) L1 of the movement unit U1.

Each one of the guide rails 7 is designed in such a way as to be moved (in the L1 direction) under the action of the associated movement unit U1.

Furthermore, each one of the guide rails 7 carries a mobile carriage 8. This mobile carriage 8 is designed to be freely mobile in the direction L2, i.e. orthogonally to the direction of movement L1 of the associated movement unit U1.

Moreover, each one of the mobile carriages 8 is provided with a rotation system 9 comprising, preferably, a ball bearing 10, which is designed to freely rotate in the plane of the upper plate 6 corresponding to the XY plane in the neutral position.

The three rotation systems 9 are each connected to the lower face 6A of the upper plate 6, by the intermediary of usual fastening elements 11 arranged in the upper plate 6.

In addition, the control module M1 comprises a closed side wall 12, which is integral with the lower plate 5, as shown in figure 4.

Consequently, a command by an operator or an automatic control system of a movement unit U1 generates the movement of the guide rail 7. During this movement of the guide rail 7, the mobile carriage 8 can be moved freely and act on the position of the upper plate 6.

Moreover, in a preferred embodiment, the second control module M2 comprises, as shown in figures 5 to 7:

- a lower plate 13 and an upper plate 14 (which corresponds to the plate 2 or to a plate whereon is fixed the plate 2);
- three movement units U2 designed to generate a translational movement. The three movement units U2 are fixed on an upper face 13A (figure 5) of the lower plate 13. The movement units U2

are, preferably, similar to the movement units U1 of the control module M1; and

- three straight guide rails 15.

Each one of the three guide rails 15 is mounted on one of
 5 the three movement units U2, to which it is associated. As such, the control module M2 comprises one guide rail 15 per movement unit U2 and each movement unit U2 is provided with a guide rail 15.

Each one of the movement units U2 is fixed on the upper
 10 face 13A in order to generate a movement in a given direction in the XY plane, as shown by the L3 direction for the movement unit U2 which can be seen on the right of figure 5.

Furthermore, each one of the guide rails 15 is arranged
 longitudinally to the direction of movement L3 of the associated
 movement unit U2. In addition, it is designed in such a way as to be
 15 moved under the action of the associated movement unit U2.

Moreover, each one of the guide rails 15 carries a mobile
 carriage 16 which is designed to be freely mobile. Each one of the guide
 rails 15 is mounted inclined, in the Z vertical direction with respect to the
 associated guide rail.

As shown in figure 6, in an XZ or YZ vertical plane, the
 20 direction of movement L4 of the freely mobile carriage 16 has an angle α , non-zero with respect to the direction of movement of the guide rail 15 (under the action of the movement unit U2). To achieve this, the guide rail 15 is connected to the movement unit U2 via a bevelled support
 25 element 17 with a triangular shape in the vertical plane.

Due to its positioning on the movement unit U2, the mobile
 carriage 17 is moved in the XY plane in the L3 direction. As shown in
 figure 5, the projection L4A of the L4 direction of movement in the XY
 plane, is parallel (or confounded) with the L3 direction.

Moreover, the mobile carriage 16 comprises a bevelled
 30 support element 18, that cooperates with the bevelled support

element 17, and which is adapted to the latter so that the upper face of the support element 18 is substantially parallel to the lower face of the support element 17.

Furthermore, each one of the carriages 18 is provided with
5 a ball 19 designed to be freely rotating.

The three balls 19 are each mounted articulated to the lower face 14A of the upper plate 14.

Due in particular to its modular architecture and to the use of movement units U1 and U2 designed to generate only translational
10 movements, the system 1 (for generating movement) such as described hereinabove is very compact, and in addition, it has an extended area of work, in particular in relation to the usual systems (in particular of the hexapod type).

In the preferred embodiment of the system 1 such as
15 described hereinabove and shown in figure 1, said system 1 comprises two control stages E1 and E2 comprising, respectively, the control modules M1 and M2 such as described hereinabove.

However, in the framework of this invention, and as specified below:

20 - the control module M1 can be carried out differently, in particular by modifying at least one of its characteristics, in particular when it must implement only some of the X_i , Y_i and θ_Z movements; and
- the system for generating movement 1 can comprise only one of these two control modules M1 and M2, which is then associated
25 with one or several auxiliary control stages.

As such, in a first alternative embodiment with respect to that of the aforementioned figures 2 to 4, the control module M1 is designed to generate only X_i and Y_i movements.

In this first alternative embodiment (specifically not shown),
30 the control module M1 comprises only two movement units U1, as well as

a straight auxiliary guide rail. This auxiliary guide rail replaces the third movement unit U1 of the embodiments of figures 2 to 4.

5 The auxiliary guide rail is arranged in a direction different from the directions of movement of the two movement units and identical to that of the third movement unit of figures 2 to 4.

In addition, the guide rail carries a mobile carriage designed to be freely mobile, and the auxiliary guide rail is arranged in such a way that the mobile carriage can be moved, freely, in the direction of movement of said third replaced movement unit.

10 The three mobile carriages are directly fixed on the lower face 6A of the upper plate 6 and are not provided with a rotation system.

The movement module in accordance with this first alternative embodiment can be associated within a system for generating movement:

- 15 - with a first auxiliary control stage, which is designed to generate, in a usual manner, a θZ movement in such a way as to obtain a system for generating X_i , Y_i and θZ movements;
- with a second auxiliary control stage, which is designed to generate, in a usual manner, a Z_i movement in such a way as to obtain a
- 20 system for generating movements in X_i , Y_i and Z_i ; or
- simultaneously to said first and second auxiliary control stages.

Furthermore, in a second alternative embodiment, the first control module M1 is designed to generate only Y_i and θZ movements.

25 In this second alternative embodiment, the control module M1 comprises two movement units U1, as well as a straight auxiliary guide rail.

The auxiliary guide rail is arranged in a direction different from the directions of movement of the two movement units and identical

30 to that of the third movement unit of figures 2 to 4.

In addition, the auxiliary guide rail as well as the two movement units each carries a mobile carriage designed to be freely mobile.

5 In this case, each one of the three mobile carriages, similar for example to the mobile carriage 8, is provided with a rotation system designed to be freely rotating in the plane XY, such as the aforementioned rotation system 9.

In addition, the three rotation systems are each connected to the lower face 6A of the upper plate 6A.

10 In association with this second embodiment, the system 1 can comprise, in a particular embodiment, an auxiliary control stage E3 shown as a thin line (for the purpose of illustration) in figure 2. This auxiliary control stage E3 is designed to generate an Xi movement of said control module M1.

15 This auxiliary control stage E3 can comprise a movement element 20 in order to generate the Xi movement. In a particular embodiment, the movement element 20 is provided with a guide rail 21 carrying a mobile carriage 22, and means for controlling the movement (not shown) of the mobile carriage 22 on the guide rail 21, 20 such as an electric motor for example.

The mobile carriage 22 is therefore mounted mobile on the guide rail 21 and it carries the control module M1 in accordance with the second alternative embodiment.

25 Moreover, in another alternative embodiment (shown in figures 7 and 8), the system for generating movement comprises, associated with the control module M2, instead of the control module M1, at least one (but preferably several) of the following three auxiliary control stages:

30 - an auxiliary control stage E5 designed to generate an Xi movement;

- an auxiliary control stage E4 designed to generate a Y_i movement; and
- an auxiliary control stage E6 designed to generate a θZ movement.

5 All of the combinations of the control module M2 with one or several of the auxiliary control stages E4 to E6 are possible, according to the applications considered (and of the movements that are to be controlled).

10 As such, in a first embodiment shown in figure 7, the system for generating movement comprises the two auxiliary control stages E4 and E5, which are shown as a thin line in this figure 7.

The auxiliary control stage E4 can comprise a movement element 23 in order to generate the Y_i movement. In a particular embodiment, the movement element 23 is provided with a guide rail 25 carrying a mobile carriage 26, and means for controlling the movement (not shown) of the mobile carriage 26 on the guide rail 25, such as an electric motor for example, which can be controlled, in a usual manner, by an operator or by an automatic control system. The mobile carriage 26 is therefore mounted mobile on the guide rail 25 and it carries the auxiliary control stage E5.

20 The auxiliary control stage E5 can comprise a movement element 24 in order to generate the X_i movement. In a particular embodiment, the movement element 24 is also provided with a guide rail 27 also carrying a mobile carriage 28, and means for controlling the movement (not shown) of the mobile carriage 28 on the guide rail 27, such as an electric motor for example, which can be controlled, usually, by an operator or by an automatic control system. The mobile carriage 28 is therefore mobile on the guide rail 27 and it carries the control module M2.

The system for generating movement according to this first embodiment is therefore able to generate X_i , Y_i , Z_i , θX and θY movements.

5 Furthermore, in a second preferred embodiment, shown in figure 8, the system for generating movement comprises, associated with the control module M2, simultaneously the three auxiliary control stages E4, E5 and E6, which are shown as a thin line in this figure 8. The auxiliary control stages E4 and E5 are similar to those of figure 7.

10 As for the auxiliary control stage E6, it can comprise an element for driving a rotation 29, for example a motor, in order to generate the θZ movement, i.e. in order to generate a rotation around the Z axis. In the example shown in figure 8, the element for driving a rotation 29 (which can usually be controlled by an operator or by an automatic control system), is mounted on the upper plate 14 of the control module M2.
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The system for generating movement according to this second embodiment is therefore able to generate the X_i , Y_i , Z_i , θX , θY and θZ movements (i.e. movements in six degrees of freedom).

Claims

1. System for generating the movement of a support plate, the support plate (2) being, in a so-called neutral position, substantially parallel to an XY plane defined by a so-called X direction and a so-called Y direction, said system (1) being configured to be able to move said support plate (2) in at least some of the six degrees of freedom, said six
 5 degrees of freedom corresponding, respectively, to a so-called X_i translation along the X direction and a so-called θ_X rotation around this X direction, to a so-called Y_i translation along the Y direction and a so-called θ_Y rotation around this Y direction, to a so-called Z_i translation
 10 along a so-called Z direction and a so-called θ_Z rotation around this Z direction, with the Z direction being orthogonal to said X and Y directions, said system comprising at least two control stages (E1, E2) superimposed in a direction Z and being secured to each other, at least one of said control stages (E1, E2) comprising a control module (M1,
 15 M2),

characterised in that said at least one control module (M1, M2) comprises only movement units (U1, U2) designed so as to each generate a translational movement of the support plate (2) in the XY plane, and this respectively in different directions, and in that said at least
 20 one control module, called first control module (M1), comprises:

- a first lower plate (5) and a first upper plate (6);
- at least two movement units (U1), the movement units (U1) being fixed on an upper face (5A) of the first lower plate (5);
 and
- 25 - straight guide rails (7), each one of said guide rails (7) being mounted on one of said movement units (U1) to which it is associated, each one of said guide rails (7) being arranged orthogonally to the direction of movement of the associated movement unit (U1) and being designed in such a way as to move under the action of the
 30 associated movement unit (U1), each one of said guide rails (7) carrying

a mobile carriage (8) which is designed to be freely mobile orthogonally to the direction of movement of the associated movement unit (U1), each one of said mobile carriages (8) being connected to a lower face (6A) of the first upper plate (6).

5 2. System according to claim 1, characterised in that the movement units (U1, U2) are arranged in the XY plane and positioned in such a way as to have different directions of translation that form, respectively, an angle of 120° between them.

10 3. System according to one of claims 1 and 2, characterised in that the first control module (M1) is designed to generate X_i and Y_i movements, and in that it comprises two movement units and a straight auxiliary guide rail, the auxiliary guide rail being arranged in a direction different from the directions of movement of the two movement units and carrying a mobile carriage designed to be freely mobile, the mobile
15 carriage being fixed to the lower face of the first upper plate.

 4. System according to one of claims 1 and 2, characterised in that the first control module (M1) is designed to generate Y_i and θ_Z movements, and in that it comprises two movement units and a straight auxiliary guide rail, the auxiliary guide rail being arranged in a direction
20 different from the directions of movement of the two movement units and carrying a mobile carriage designed to be freely mobile, each one of said mobile carriages being provided with a rotation system designed to rotate freely in the XY plane, the three rotation systems being connected, each one, to the lower face of the first upper plate.

25 5. System according to claim 4, characterised in that it comprises an auxiliary control stage (E3) designed to generate an X_i movement of the so-called first control module (M1).

 6. System according to one of claims 1 and 2, characterised in that the first control module (M1) is designed to generate X_i , Y_i and θ_Z
30 movements, and in that it comprises:

- three movement units (U1); and

- three straight guide rails (7), each one of said guide rails (7) being mounted on one of said movement units (U1) to which it is associated, each one of said guide rails (7) being arranged orthogonally to the direction of movement of the associated movement unit (U1) and being designed in such a way as to move under the action of the associated movement unit (U1), each one of said guide rails (7) carrying a mobile carriage (8), which is designed to be freely mobile orthogonally to the direction of movement of the associated movement unit (U1), each one of said mobile carriages (8) being provided with a rotation system (9) designed to rotate freely in the XY plane, the three rotation systems (9) being connected, each one, to the lower face (6A) of the first upper plate (6).

7. System as claimed in any preceding claim, characterised in that a second control module (M2) is designed to generate θX , θY and Z_i movements, and in that it comprises:

- a second lower plate (13) and a second upper plate (14);
- three movement units (U2) designed so as to generate a translational movement, the movement units (U2) being fixed on an upper face (13A) of the second lower plate (13); and
- three straight guide rails (15), each one of said guide rails (15) being mounted, in an inclined manner with respect to the XY plane, on one of said movement units (U2) to which it is associated, each one of said guide rails (15) being arranged longitudinally to the direction of movement of the associated movement unit (U2) and being designed in such a way as to move under the action of the associated movement unit (U2), each one of said guide rails (15) carrying a mobile carriage (16) which is designed to be freely mobile, each one of said mobile carriages (16) being provided with a ball (19) designed to be freely rotating, the three balls (19) being articulated, each one, to the lower face (14A) of the first upper plate (14).

8. System according to claim 7, characterised in that it comprises, in addition, at least one of the following three auxiliary control stages:

- 5 - an auxiliary control stage (E5) designed to generate an X_i movement;
- an auxiliary control stage (E4) designed to generate a Y_i movement; and
- an auxiliary control stage (E6) designed to generate a θZ movement.

10 9. System according to claims 6 and 7, characterised in that it comprises only two control stages (E1, E2), of which one so-called lower control stage (E1) comprises the so-called first control module (M1) designed to generate X_i , Y_i and θZ movements, and of which a so-called second control stage comprises said second control module (M2)
15 designed to generate θX , θY and Z_i movements.