

DESCRIPTION

MOVABLE BODY DRIVE METHOD AND MOVABLE BODY DRIVE
SYSTEM, PATTERN FORMATION METHOD AND APPARATUS,
5 EXPOSURE METHOD AND APPARATUS, DEVICE MANUFACTURING
METHOD, AND CALIBRATION METHOD

TECHNICAL FIELD

The present invention relates to movable body drive
10 methods and movable body drive systems, pattern formation
methods and apparatuses, exposure methods and apparatuses,
device manufacturing methods, and calibration methods, and
more particularly to a movable body drive method and a movable
body drive system in which a movable body is driven within
15 a movement plane, a pattern formation method using the movable
body drive method and a pattern formation apparatus equipped
with the movable body drive system, an exposure method using
the movable body drive method and an exposure apparatus
equipped with the movable body drive system, a device
20 manufacturing method using the pattern formation method, and
a calibration method used in an encoder system that measures
positional information of a movable body in a movement plane.

BACKGROUND ART

25 Conventionally, in a lithography process for
manufacturing microdevices (electron devices and the like)
such as semiconductor devices and liquid crystal display
devices, exposure apparatuses such as a reduction projection
exposure apparatus by a step-and-repeat method (a so-called

stepper) and a reduction projection exposure apparatus by a step-and-scan method (a so-called scanning stepper (which is also called a scanner) are relatively frequently used.

In this kind of exposure apparatus, in order to transfer
5 a pattern of a reticle (or a mask) on a plurality of shot areas on a wafer, a wafer stage holding the wafer is driven in an XY two-dimensional direction, for example, by linear motors and the like. Especially in the case of a scanning stepper, not only the wafer stage but also a reticle stage is driven
10 with predetermined strokes in a scanning direction by linear motors and the like. Position measurement of the reticle stage and the wafer stage is generally performed using a laser interferometer whose stability of measurement values is good for over a long time and has a high resolution.

15 However, requirements for a stage position control with higher precision are increasing due to finer patterns that accompany higher integration of semiconductor devices, and now, short-term variation of measurement values due to temperature fluctuation of the atmosphere on the beam optical
20 path of the laser interferometer has come to occupy a large percentage in the overlay budget.

Meanwhile, as a measurement device besides the laser interferometer used for position measurement of the stage, an encoder can be used, however, because the encoder uses a
25 scale, which lacks in mechanical long-term stability (drift of grating pitch, fixed position drift, thermal expansion and the like), it makes the encoder have a drawback of lacking measurement value linearity and being inferior in long-term stability when compared with the laser interferometer.

In view of the drawbacks of the laser interferometer and the encoder described above, various proposals are being made (refer to Patent Citation 1, Patent Citation 2 and the like) of a device that measures the position of a stage using both
5 a laser interferometer and an encoder (a position detection sensor which uses a diffraction grating) together.

Further, the measurement resolution of the conventional encoder was inferior when compared with an interferometer, however, recently, an encoder which has a nearly equal or a
10 better measurement resolution than a laser interferometer has appeared (for example, refer to Patent Citation 3), and the technology to put the laser interferometer and the encoder described above together is beginning to gather attention.

However, for example, in the case position measurement
15 of the movement plane of the wafer stage is performed of the exposure apparatus that moves two-dimensionally holding a wafer using an encoder, in order to avoid an unnecessary increase in the size of the wafer stage and the like, it becomes essential to control the movement of the wafer stage using
20 a plurality of encoders, while switching the encoder used for control during the movement of the wafer stage. That is, it becomes necessary to control the position of the wafer stage using an encoder system which includes a plurality of heads.

Patent Citation 1: Kokai (Japanese Patent Unexamined
25 Application Publication) No. 2002-151405

Patent Citation 2: Kokai (Japanese Patent Unexamined Application Publication) No. 2004-101362

Patent Citation 3: Kokai (Japanese Patent Unexamined Application Publication) No. 2005-308592

DISCLOSURE OF THE INVENTION**MEANS FOR SOLVING THE PROBLEMS**

The present invention has been made in consideration of
5 the circumstances described above, and according to a first
aspect of the present invention, there is provided a movable
body drive method in which a movable body is driven along a
substantially predetermined plane, the method comprising: a
drive process in which positional information of the movable
10 body in a first direction is measured, using at least one first
head of an encoder system that includes a plurality of first
heads which irradiates a measurement beam on a grating whose
periodic direction is the first direction parallel to the plane
and receives the beam from the grating and is arranged in a
15 direction intersecting the first direction, and the movable
body is driven along the plane, based on a measurement result
of the positional information and positional information in
a surface parallel to the plane of the measurement beam emitted
from at least one of the first heads used for the measurement
20 of the positional information.

According to this method, positional information of the
movable body in the first direction is measured using at least
one first head of the encoder system, and based on the
measurement results of the positional information and
25 positional information of the measurement beam emitted from
the at least one first head used for the measurement of the
positional information in a surface parallel to the
predetermined plane, the movable body is driven along a
predetermined plane. Accordingly, it becomes possible to

control the movement of the movable body, using the encoder system including a plurality of first heads.

According to a second aspect of the present invention, there is provided a pattern formation method, comprising: a
5 mount process in which an object is mounted on a movable body that can move in a movement plane; and a drive process in which the movable body is driven by the movable body drive method of the present invention, to form a pattern to the object.

According to this method, a desired pattern can be formed
10 on the object by forming a pattern on the object mounted on the movable body, which is driven using any one of the movable body drive methods of the present invention.

According to a third aspect of the present invention, there is provided a first device manufacturing method
15 including a pattern formation process wherein in the pattern formation process, a pattern is formed on an object using the pattern formation method of the present invention.

According to a fourth aspect of the present invention, there is provided a first exposure method in which a pattern
20 is formed on an object by an irradiation of an energy beam wherein for relative movement of the energy beam and the object, a movable body on which the object is mounted is driven, using the movable body drive method according of the present invention.

25 According to this method, for relative movement between an energy beam irradiated on the object and the object, the movable body on which the object is mounted is driven with good precision, using any one of the movable body drive methods of the present invention. Accordingly, it becomes possible

to form a desired pattern on the object by scanning exposure

According to a fifth aspect of the present invention,
there is provided a second exposure method of exposing an
object with an energy beam, the method comprising: mounting
5 the object on a movable body that can move at least in a first
and second direction orthogonal in a predetermined plane, and
controlling a position of the movable body in the predetermined
plane, based on measurement information of an encoder system,
which has one of a grating section and a head unit arranged
10 on a surface of the movable body where the object is mounted
and the other also arranged facing the surface of the movable
body and also measures positional information of the movable
body in the predetermined plane with a head that faces the
grating section among a plurality of heads of the head unit,
15 and positional information of a detection point of the head
used for the measurement in a surface parallel to the
predetermined plane.

According to this method, it becomes possible to control
the position of the movable body in the predetermined plane
20 using the encoder system including a plurality of heads with
good precision, without being affected by the measurement
error of the encoder system due to the position of the detection
point of each head, which in turn, makes it possible to expose
the object on the movable body with high precision.

25 According to a sixth aspect of the present invention,
there is provided a third exposure method of exposing an object
with an energy beam, the method comprising: mounting the object
on a movable body that can move at least in a first and second
direction orthogonal in a predetermined plane; measuring

positional information of the movable body using an encoder system, which has one of a grating section and a head unit arranged on a surface of the movable body where the object is held and the other is also arranged facing the surface of the movable body and measures positional information of the movable body in the predetermined plane with a head that faces the grating section among a plurality of heads of the head unit; and controlling the position of the movable body in the predetermined plane, based on correction information to compensate for the measurement error of the encoder system that occurs due to the position or displacement of the detection point of the head used for the measurement and measurement information of the encoder system.

According to this method, it becomes possible to control the position of the movable body in the predetermined plane using the encoder system with good precision, without being affected by the measurement error of the encoder system that occurs due to the position or displacement of the detection point of each head used for the measurement, which in turn, makes it possible to expose the object on the movable body with high precision.

According to a seventh aspect of the present invention, there is provided a second device manufacturing method including a lithography process wherein in the lithography process, an exposure method according to one of the second and third exposure method of the present invention is used to expose a sensitive object mounted on the movable body, and to form a pattern on the sensitive object.

According to an eighth aspect of the present invention,

there is provided a movable body drive system in which a movable body is driven along a substantially predetermined plane, the system comprising: a grating whose periodic direction is a first direction parallel to the plane; an encoder system which includes a plurality of first heads that irradiates a measurement beam on the grating and receives the beam from the grating, arranged in a direction intersecting the first direction; and a controller which measures positional information of the movable body in the first direction using at least one first head of the plurality of first heads and drives the movable body along the plane, based on the measurement result of the positional information and positional information of the measurement beam emitted from the at least one first head used for measurement of the positional information in a surface parallel to the plane.

According to this system, the controller measures the positional information of the movable body in the first direction using at least one first head of the encoder system, and based on the measurement results of the positional information and positional information of the measurement beam emitted from the at least one first head used for measurement of the positional information in the surface parallel to the predetermined plane, the movable body is driven along the predetermined plane. Accordingly, it becomes possible to control the movement of the movable body, using the encoder system including a plurality of first heads.

According to a ninth aspect of the present invention, there is provided a pattern formation apparatus, the apparatus comprising: a movable body on which the object is mounted,

and is movable in a movement plane holding the object; and a movable body drive system of the present invention that drives the movable body to perform pattern formation with respect to the object.

5 According to this apparatus, by generating a pattern on the object on the movable body driven by the movable body drive systems of the present invention with a patterning device, it becomes possible to form a desired pattern on the object.

 According to a tenth aspect of the present invention,
10 there is provided a first exposure apparatus that forms a pattern on an object by an irradiation of an energy beam, the apparatus comprising: a patterning device that irradiates the energy beam on the object; and the movable body drive system according to the present invention, whereby the movable body
15 drive system drives the movable body on which the object is mounted for relative movement of the energy beam and the object.

 According to this apparatus, for relative movement of the energy beam irradiated on the object from the patterning
20 device and the object, the movable body on which the object is mounted is driven by the movable body drive system of the present invention. Accordingly, it becomes possible to form a desired pattern on the object by scanning exposure.

 According to an eleventh aspect of the present invention,
25 there is provided a second exposure apparatus that exposes an object with an energy beam, the apparatus comprising: a movable body that holds the object and is movable at least in a first and second directions which are orthogonal in a predetermined plane; an encoder system in which one of a

grating section and a head unit is arranged on a surface of the movable body where the object is held and the other is arranged facing the surface of the movable body, and positional information of the movable body in the predetermined plane is measured by a head that faces the grating section of a plurality of heads of the head unit; and a controller that controls a position of the movable body in the predetermined plane, based on measurement information of the encoder system and positional information of a detection point of the head used for the measurement in a surface parallel to the predetermined plane.

According to this method, it becomes possible to control the position of the movable body in the predetermined plane using the encoder system including a plurality of heads with good precision, without being affected by the measurement error of the encoder system due to the position of the detection point of each head, which in turn, makes it possible to expose the object on the movable body with high precision.

According to a twelfth aspect of the present invention, there is provided a third exposure apparatus that exposes an object with an energy beam, the apparatus comprising: a movable body that holds the object and is movable at least in a first and second directions which are orthogonal in a predetermined plane; an encoder system in which one of a grating section and a head unit is arranged on a surface of the movable body where the object is held and the other is arranged facing the surface of the movable body, and positional information of the movable body in the predetermined plane is measured by a head that faces the grating section of a plurality of heads

of the head unit; and a controller that controls the position of the movable body in the predetermined plane, based on correction information to compensate for the measurement error of the encoder system that occurs due to the position or displacement of the detection point of the head used for the measurement and measurement information of the encoder system.

According to this method, it becomes possible to control the position of the movable body in the predetermined plane using the encoder system with good precision, without being affected by the measurement error of the encoder system that occurs due to the position or displacement of the detection point of head used for the measurement, which in turn, makes it possible to expose the object on the movable body with high precision.

According to a thirteenth aspect of the present invention, there is provided a calibration method used in an encoder system that measures positional information of a movable body that moves along a substantially predetermined plane in a surface parallel to the plane, the method comprising: an acquisition process in which the movable body is rotated at a predetermined angle in the surface parallel to the plane and a measurement value of a head of the encoder system that measures the positional information of the movable body in a measurement direction parallel to the plane and a measurement value of a measurement device that measures a rotation angle of the movable body in the surface parallel to the plane are acquired; and a computing process in which positional information of a measurement beam emitted from the

head in a direction perpendicular to the measurement direction in the surface parallel to the plane is computed, based on the measurement value of the head that has been acquired and the rotation angle that has been measured by the measurement
5 device.

According to this method, the movable body is rotated at a predetermined angle in the surface parallel to the plane and the measurement value of the head of the encoder system that measures the positional information of the movable body
10 in the measurement direction parallel to the plane and the measurement value of the measurement device that measures a rotation angle of the movable body in the surface parallel to the plane are acquired, and based on the measurement value of the head that has been acquired and the rotation angle that
15 has been measured by the measurement device, positional information of the measurement beam emitted from the head in the direction perpendicular to the measurement direction in the surface parallel to the plane is computed. Accordingly, it becomes possible to calibrate the positional information
20 of the measurement beam emitted from a head in a direction perpendicular to the measurement direction, which shows a tendency of having an error to the design value larger than the measurement direction of the head, with good precision.

25 **BRIEF DESCRIPTION OF THE DRAWINGS**

FIG. 1 is a view schematically showing the configuration of an exposure apparatus related to an embodiment.

FIG. 2 is a plan view showing a stage device in FIG. 1.

FIG. 3 is a plan view showing the placement of various

measuring apparatuses (such as encoders, alignment systems, a multipoint AF system, and Z sensors) that are equipped in the exposure apparatus in FIG. 1.

FIG. 4A is a plan view showing a wafer stage, and FIG. 4B is a schematic side view of a partially sectioned wafer stage WST.

FIG. 5A is a plan view showing a measurement stage, and FIG. 5B is a schematic side view showing a partial cross section of the measurement stage.

FIG. 6 is a block diagram showing a main configuration of a control system of the exposure apparatus related to an embodiment.

FIGS. 7A and 7B are views for describing position measurement of the wafer table in the XY plane by a plurality of encoders which respectively include a plurality of heads placed in the shape of an array and a carryover of the measurement value between the heads.

FIG. 8A is a view showing an example of a configuration of an encoder, and FIG. 8B is a view used to describe a mechanism of the generation of this measurement error and is a view for describing a relation between an incident light and a diffracted light of the beam in the encoder head with respect to the reflection grating.

FIG. 9A is a view showing a case when a measurement value does not change even if a relative movement in a non-measurement direction occurs between a head of an encoder and a scale, and FIG. 9B is a view showing a case when a measurement value changes when a relative movement in a non-measurement direction occurs between a head of an encoder

and a scale.

FIGS. 10A to 10D are views used for describing the case when the measurement value of the encoder changes and the case when the measurement values do not change, when a relative
5 movement in the non-measurement direction occurs between the head and the scale.

FIGS. 11A and 11B are views for explaining an operation to acquire correction information to correct a measurement error of an encoder (a first encoder) due to the relative
10 movement of the head and the scale in the non-measurement direction.

FIG. 12 is a graph showing a measurement error of the encoder with respect to the change in the Z position in pitching amount $\theta x = \alpha$.

15 FIG. 13 is a view for explaining an operation to acquire correction information to correct a measurement error of another encoder (a second encoder) due to the relative movement of the head and the scale in the non-measurement direction.

FIG. 14 is a view for describing a calibration process
20 of a head position.

FIG. 15 is a view for explaining an inconvenience that occurs in the case a plurality of measurement points on the same scale is measured by a plurality of heads.

FIG. 16 is a view for explaining a method to measure the
25 unevenness of the scale (No. 1).

FIGS. 17A to 17D are views for explaining a method to measure the unevenness of the scale (No. 2).

FIG. 18 is a view for describing an acquisition operation of correction information of the grating pitch of the scale

and the correction information of the grating deformation.

FIGS. 19A and 19B are views for explaining a concrete method to convert a measurement value of the encoder that has been corrected into a position of wafer stage WST.

5 FIG. 20 is view to explain the switching process of the encoder used for the position control in the XY plane of the wafer stage.

FIG. 21 is a view conceptually showing position control of the wafer stage, intake of the measurement value of the encoder, and an encoder switching timing.

FIG. 22 is a view showing a state of the wafer stage and the measurement stage while exposure by a step-and-scan method is being performed to a wafer on the wafer stage.

FIG. 23 is a view showing the state of both stages just after the stages shifted from a state where the wafer stage and the measurements stage are distanced to a state where both stages are in contact after exposure has been completed.

FIG. 24 is a view showing a state where the measurement stage moves in the -Y-direction and the wafer stage moves toward an unloading position, while maintaining the positional relation between the wafer table and the measurement table in the Y-axis direction.

FIG. 25 is a view showing a state of the wafer stage and the measurement stage when the measurement stage has reached a position where a Sec-BCHK (interval) is performed.

FIG. 26 is a view showing a state of the wafer stage and the measurement stage when the wafer stage has moved from the unloading position to a loading position in parallel with the Sec-BCHK (interval) being performed.

FIG. 27 is a view showing a state of the wafer stage and the measurement stage when the measurement stage moves to an optimal scrub waiting position and a wafer is loaded on a wafer table.

5 FIG. 28 is a view showing a state of both stages when the wafer stage has moved to a position where the Pri-BCHK former process is performed while the measurement stage is waiting at the optimal scrub waiting position.

10 FIG. 29 is a view showing a state of the wafer stage and the measurement stage when alignment marks arranged in three first alignment shot areas are being simultaneously detected using alignment systems AL1, AL2₂ and AL2₃.

15 FIG. 30 is a view showing a state of the wafer stage and the measurement stage when the focus calibration former process is being performed.

FIG. 31 is a view showing a state of the wafer stage and the measurement stage when alignment marks arranged in five second alignment shot areas are being simultaneously detected using alignment systems AL1 and AL2₁ to AL2₄.

20 FIG. 32 is a view showing a state of the wafer stage and the measurement stage when at least one of the Pri-BCHK latter process and the focus calibration latter process is being performed.

25 FIG. 33 is a view showing a state of the wafer stage and the measurement stage when alignment marks arranged in five third alignment shot areas are being simultaneously detected using alignment systems AL1 and AL2₁ to AL2₄.

FIG. 34 is a view showing a state of the wafer stage and the measurement stage when alignment marks arranged in three

fourth alignment shot areas are being simultaneously detected using alignment systems AL1, AL2₂ and AL2₃.

FIG. 35 is a view showing a state of the wafer stage and the measurement stage when the focus mapping has ended.

5 FIG. 36 is a flow chart for explaining an embodiment of the device manufacturing method.

FIG. 37 is a flowchart used to explain a specific example of step 204 in FIG. 36.

10 **BEST MODE FOR CARRYING OUT THE INVENTION**

An embodiment of the present invention will be described below, with reference to FIGS. 1 to 35.

FIG. 1 schematically shows a configuration of an exposure apparatus 100 related to the embodiment. Exposure
15 apparatus 100 is a scanning exposure apparatus of the step-and-scan method, namely the so-called scanner. As it will be described later, a projection optical system PL is arranged in the embodiment, and in the description below, a direction parallel to an optical axis AX of projection optical
20 system PL will be described as the Z-axis direction, a direction within a plane orthogonal to the Z-axis direction in which a reticle and a wafer are relatively scanned will be described as the Y-axis direction, a direction orthogonal to the Z-axis and the Y-axis will be described as the X-axis
25 direction, and rotational (inclination) directions around the X-axis, the Y-axis, and the Z-axis will be described as θx , θy , and θz directions, respectively.

Exposure apparatus 100 includes an illumination system
10, a reticle stage RST that holds a reticle R that is

illuminated by an illumination light for exposure
(hereinafter, referred to as an "illumination light" or
"exposure light") IL from illumination system 10, a projection
unit PU that includes projection optical system PL that
5 projects illumination light IL emitted from reticle R on a
wafer W, a stage device 50 that has a wafer stage WST and a
measurement stage MST, their control system, and the like.
On wafer stage WST, wafer W is mounted.

Illumination system 10 includes a light source and an
10 illumination optical system that has an illuminance
uniformity optical system that includes an optical integrator
and the like and a reticle blind and the like (none of which
are shown), as is disclosed in, for example, Kokai (Japanese
Patent Unexamined Application Publication) No. 2001-313250
15 (the corresponding U.S. Patent Application Publication
No.2003/0025890) and the like. In illumination system 10, a
slit-shaped illumination area extending in the X-axis
direction which is set on reticle R with a reticle blind (a
masking system) is illuminated by illumination light
20 (exposure light) IL with a substantially uniform illuminance.
In this case, as illumination light IL, for example, an ArF
excimer laser beam (wavelength 193 nm) is used. Further, as
the optical integrator, for example, a fly-eye lens, a rod
integrator (an internal reflection type integrator), a
25 diffractive optical element or the like can be used.

On reticle stage RST, reticle R on which a circuit
pattern or the like is formed on its pattern surface (the lower
surface in FIG. 1) is fixed, for example, by vacuum chucking.
Reticle stage RST is finely drivable or movable in within an

XY plane by a reticle stage drive system 11 (not shown in FIG. 1, refer to FIG. 6) that includes a linear motor or the like, and reticle stage RST is also drivable in a predetermined scanning direction (the Y-axis direction, which is the lateral
5 direction of the page surface in FIG. 1) at a designated scanning speed.

Positional information (including rotation information in the θ z direction) of reticle stage RST in the movement plane is constantly detected, for example, at a resolution
10 of around 0.5 to 1 nm by a reticle laser interferometer (hereinafter referred to as a "reticle interferometer") 116, via a movable mirror 15 (the mirrors actually arranged are a Y movable mirror that has a reflection surface which is orthogonal to the Y-axis direction and an X movable mirror
15 that has a reflection surface orthogonal to the X-axis direction). The measurement values of reticle interferometer 116 are sent to a main controller 20 (not shown in FIG. 1, refer to FIG. 6). Main controller 20 computes the position of reticle stage RST in the X-axis direction, Y-axis direction,
20 and the θ z direction based on the measurement values of reticle interferometer 116, and also controls the position (and velocity) of reticle stage RST by controlling reticle stage drive system 11 based on the computation results.

Incidentally, instead of movable mirror 15, the edge surface
25 of reticle stage RST can be mirror polished so as to form a reflection surface (corresponding to the reflection surface of movable mirror 15). Further, reticle interferometer 116 can measure positional information of reticle stage RST related to at least one of the Z-axis, θ x, and θ y directions.

Projection unit PU is placed below reticle stage RST in FIG. 1. Projection unit PU includes a barrel 40, and projection optical system PL that has a plurality of optical elements which are held in a predetermined positional relation inside barrel 40. As projection optical system PL, for example, a dioptric system is used, consisting of a plurality of lenses (lens elements) that is disposed along an optical axis AX, which is parallel to the Z-axis direction. Projection optical system PL is, for example, a both-side telecentric dioptric system that has a predetermined projection magnification (such as one-quarter, one-fifth, or one-eighth times). Therefore, when illumination light IL from illumination system 10 illuminates illumination area IAR, a reduced image of the circuit pattern (a reduced image of a part of the circuit pattern) of the reticle is formed within illumination area IAR, with illumination light IL that has passed through reticle R which is placed so that its pattern surface substantially coincides with a first plane (an object plane) of projection optical system PL, in an area IA (exposure area) conjugate to illumination area IAR on wafer W whose surface is coated with a resist (a sensitive agent) and is placed on a second plane (an image plane) side, via projection optical system PL (projection unit PU) and liquid Lq (refer to FIG. 1). And by reticle stage RST and wafer stage WST being synchronously driven, the reticle is relatively moved in the scanning direction (the Y-axis direction) with respect to illumination area IAR (illumination light IL) while wafer W is relatively moved in the scanning direction (the Y-axis direction) with respect to the exposure area (illumination

light IL), thus scanning exposure of a shot area (divided area) on wafer W is performed, and the pattern of the reticle is transferred onto the shot area. That is, in the embodiment, the pattern is generated on wafer W according to illumination system 10, the reticle, and projection optical system PL, and then by the exposure of the sensitive layer (resist layer) on wafer W with illumination light IL, the pattern is formed on wafer W. Although it is not shown in the drawings, projection unit PU is mounted on a barrel platform supported by three struts via a vibration isolation mechanism, however, as is disclosed in, for example, the pamphlet of International Publication No. WO 2006/038952, projection unit PU can be supported by suspension with respect to a mainframe member (not shown) placed above projection unit PU or with respect to a base member on which reticle stage RST is placed.

Further, in exposure apparatus 100 of the embodiment, in order to perform exposure applying the liquid immersion method, a nozzle unit 32 that constitutes a part of a local liquid immersion device 8 is arranged so as to enclose the periphery of the lower end portion of barrel 40 that holds an optical element that is closest to an image plane side (wafer W side) that constitutes projection optical system PL, which is a lens (hereinafter, also referred to a "tip lens") 191 in this case. In the embodiment, as shown in FIG. 1, the lower end surface of nozzle unit 32 is set to be substantially flush with the lower end surface of tip lens 191. Further, nozzle unit 32 is equipped with a supply opening and a recovery opening of liquid Lq, a lower surface to which wafer W is placed facing and at which the recovery opening is arranged, and a supply

flow channel and a recovery flow channel that are connected to a liquid supply pipe 31A and a liquid recovery pipe 31B respectively. As shown in FIG. 3, liquid supply pipe 31A and liquid recovery pipe 31B are inclined at an angle of 45 degrees with respect to the X-axis direction and the Y-axis direction in a planar view (when viewed from above) and are symmetrically placed with respect to a straight line LV in the Y-axis direction that passes through optical axis AX of projection optical system PL.

One end of a supply pipe (not shown) is connected to liquid supply pipe 31A while the other end of the supply pipe is connected to a liquid supply device 5 (not shown in FIG. 1, refer to FIG. 6), and one end of a recovery pipe (not shown) is connected to liquid recovery pipe 31B while the other end of the recovery pipe is connected to a liquid recovery device 6 (not shown in FIG. 1, refer to FIG. 6).

Liquid supply device 5 includes a liquid tank, a compression pump, a temperature controller, a valve for controlling supply/stop of the liquid to liquid supply pipe 31A, and the like. As the valve, for example, a flow rate control valve is preferably used so that not only the supply/stop of the liquid but also the adjustment of flow rate can be performed. The temperature controller adjusts the temperature of the liquid within the liquid tank to nearly the same temperature, for example, as the temperature within the chamber (not shown) where the exposure apparatus is housed. Incidentally, the tank for supplying the liquid, the compression pump, the temperature controller, the valve, and the like do not all have to be equipped in exposure apparatus

100, and at least a part of them can also be substituted by the equipment available in the plant or the like where exposure apparatus 100 is installed.

Liquid recovery device 6 includes a liquid tank, a
5 suction pump, a valve for controlling recovery/stop of the liquid via liquid recovery pipe 31B, and the like. As the valve, a flow rate control valve is preferably used corresponding to the valve of liquid supply device 5. Incidentally, the tank for recovering the liquid, the suction pump, the valve, and
10 the like do not all have to be equipped in exposure apparatus 100, and at least a part of them can also be substituted by the equipment available in the plant or the like where exposure apparatus 100 is installed.

In the embodiment, as the liquid described above, pure
15 water (hereinafter, it will simply be referred to as "water" besides the case when specifying is necessary) that transmits the ArF excimer laser light (light with a wavelength of 193 nm) is to be used. Pure water can be obtained in large quantities at a semiconductor manufacturing plant or the like
20 without difficulty, and it also has an advantage of having no adverse effect on the photoresist on the wafer, to the optical lenses or the like.

Refractive index n of the water with respect to the ArF excimer laser light is around 1.44. In the water the
25 wavelength of illumination light IL is $193 \text{ nm} \times 1/n$, shorted to around 134 nm.

Liquid supply device 5 and liquid recovery device 6 each have a controller, and the respective controllers are controlled by main controller 20 (refer to FIG. 6). According

to instructions from main controller 20, the controller of liquid supply device 5 opens the valve connected to liquid supply pipe 31A to a predetermined degree to supply water Lq (refer to FIG. 1) to the space between tip lens 191 and wafer W via liquid supply pipe 31A, the supply flow channel and the supply opening. Further, when the water is supplied, according to instructions from main controller 20, the controller of liquid recovery device 6 opens the valve connected to liquid recovery pipe 31B to a predetermined degree to recover water Lq from the space between tip lens 191 and wafer W into liquid recovery device 6 (the liquid tank) via the recovery opening, the recovery flow channel and liquid recovery pipe 31B. During the supply and recovery operations, main controller 20 gives commands to the controllers of liquid supply device 5 and liquid recovery device 6 so that the quantity of water Lq supplied to the space between tip lens 191 and wafer W constantly equals the quantity of water Lq recovered from the space. Accordingly, a constant quantity of water Lq is held (refer to FIG. 1) in the space between tip lens 191 and wafer W. In this case, water Lq held in the space between tip lens 191 and wafer W is constantly replaced.

As is obvious from the above description, in the embodiment, local liquid immersion device 8 is configured including nozzle unit 32, liquid supply device 5, liquid recovery device 6, liquid supply pipe 31A and liquid recovery pipe 31B, and the like. Local liquid immersion device 8 fills liquid Lq in the space between tip lens 191 and wafer W by nozzle unit 32, so that a local liquid immersion space (equivalent to a liquid immersion area 14) which includes the

optical path space of illumination light IL is formed. Accordingly, nozzle unit 32 is also called a liquid immersion space formation member or a containment member (or, a confinement member). Incidentally, a part of local liquid immersion device 8, for example, at least nozzle unit 32 may also be supported in a suspended state by a main frame (including the barrel platform described earlier) that holds projection unit PU, or may also be arranged at another frame member that is separate from the main frame. Or, in the case projection unit PU is supported in a suspended state as is described earlier, nozzle unit 32 may also be supported in a suspended state integrally with projection unit PU, but in the embodiment, nozzle unit 32 is arranged on a measurement frame that is supported in a suspended state independently from projection unit PU. In this case, projection unit PU does not have to be supported in a suspended state.

Incidentally, also in the case measurement stage MST is located below projection unit PU, the space between a measurement table (to be described later) and tip lens 191 can be filled with water Lq in a similar manner to the manner described above.

Incidentally, in the description above, one liquid supply pipe (nozzle) and one liquid recovery pipe (nozzle) were arranged as an example, however, the present invention is not limited to this, and a configuration having multiple nozzles as is disclosed in, for example, the pamphlet of International Publication No. WO 99/49504, may also be employed, in the case such an arrangement is possible taking into consideration a relation with adjacent members. Further,

the lower surface of nozzle unit 32 can be placed near the image plane (more specifically, a wafer) of projection optical system PL rather than the outgoing plane of tip lens 191, or, in addition to the optical path of the image plane side of tip lens 191, a configuration in which the optical path on the object plane side of tip lens 191 is also filled with liquid can be employed. The point is that any configuration can be employed, as long as the liquid can be supplied in the space between optical member (tip lens) 191 in the lowest end constituting projection optical system PL and wafer W. For example, the liquid immersion mechanism disclosed in the pamphlet of International Publication No. WO 2004/053955, or the liquid immersion mechanism disclosed in the EP Patent Application Publication No. 1 420 298 can also be applied to the exposure apparatus of the embodiment.

Referring back to FIG. 1, stage device 50 is equipped with wafer stage WST and measurement stage MST that are placed above a base board 12, an interferometer system 118 (refer to FIG. 6) including Y interferometers 16 and 18, and the like that measure positional information of stages WST and MST, an encoder system (to be described later) that is used for measuring positional information of wafer stage WST on exposure or the like, a stage drive system 124 (refer to FIG. 6) that drives stages WST and MST, and the like.

On the bottom surface of each of wafer stage WST and measurement stage MST, a noncontact bearing (not shown), for example, a vacuum preload type hydrostatic air bearing (hereinafter, referred to as an "air pad") is arranged at a plurality of points. Wafer stage WST and measurement stage

MST are supported in a noncontact manner via a clearance of around several μm above base board 12, by static pressure of pressurized air that is blown out from the air pad toward the upper surface of base board 12. Further, stages WST and MST
5 are independently drivable in two-dimensional directions, which are the Y-axis direction (a horizontal direction of the page surface of FIG. 1) and the X-axis direction (an orthogonal direction to the page surface of FIG. 1) in a predetermined plane (the XY plane), by stage drive system 124.

10 To be more specific, on a floor surface, as shown in the plan view in FIG. 2, a pair of Y-axis stators 86 and 87 extending in the Y-axis direction are respectively placed on one side and the other side in the X-axis direction with base board 12 in between. Y-axis stators 86 and 87 are each composed of,
15 for example, a magnetic pole unit that incorporates a permanent magnet group that is made up of a plurality of sets of a north pole magnet and a south pole magnet that are placed at a predetermined distance and alternately along the Y-axis direction. At Y-axis stators 86 and 87, two Y-axis movers 82
20 and 84, and two Y-axis movers 83 and 85 are respectively arranged in a noncontact engaged state. In other words, four Y-axis movers 82, 84, 83 and 85 in total are in a state of being inserted in the inner space of Y-axis stator 86 or 87 whose XZ sectional surface has a U-like shape, and are
25 severally supported in a noncontact manner via a clearance of, for example, around several μm via the air pad (not shown) with respect to corresponding Y-axis stator 86 or 87. Each of Y-axis movers 82, 84, 83 and 85 is composed of, for example, an armature unit that incorporates armature coils placed at

a predetermined distance along the Y-axis direction. That is, in the embodiment, Y-axis movers 82 and 84 made up of the armature units and Y-axis stator 86 made up of the magnetic pole unit constitute moving coil type Y-axis linear motors respectively. Similarly, Y-axis movers 83 and 85 and Y-axis stator 87 constitute moving coil type Y-axis linear motors respectively. In the following description, each of the four Y-axis linear motors described above is referred to as a Y-axis linear motor 82, a Y-axis linear motor 84, a Y-axis linear motor 83 and a Y-axis linear motor 85 as needed, using the same reference codes as their movers 82, 84, 83 and 85.

Movers 82 and 83 of two Y-axis linear motors 82 and 83 out of the four Y-axis linear motors are respectively fixed to one end and the other end in a longitudinal direction of an X-axis stator 80 that extends in the X-axis direction. Further, movers 84 and 85 of the remaining two Y-axis linear motors 84 and 85 are fixed to one end and the other end of an X-axis stator 81 that extends in the X-axis direction. Accordingly, X-axis stators 80 and 81 are driven along the Y-axis by a pair of Y-axis linear motors 82 and 83 and a pair of Y-axis linear motors 84 and 85 respectively.

Each of X-axis stators 80 and 81 is composed of, for example, an armature unit that incorporates armature coils placed at a predetermined distance along the X-axis direction.

One X-axis stator, X-axis stator 81 is arranged in a state of being inserted in an opening (not shown) formed at a stage main section 91 (not shown in FIG. 2, refer to FIG. 1) that constitutes a part of wafer stage WST. Inside the opening of stage main section 91, for example, a magnetic pole

unit, which has a permanent magnet group that is made up of a plurality of sets of a north pole magnet and a south pole magnet placed at a predetermined distance and alternately along the X-axis direction, is arranged. This magnetic pole unit and X-axis stator 81 constitute a moving magnet type X-axis linear motor that drives stage main section 91 in the X-axis direction. Similarly, the other X-axis stator, X-axis stator 80 is arranged in a state of being inserted in an opening formed at a stage main section 92 (not shown in FIG. 2, refer to FIG. 1) that constitutes a part of measurement stage MST. Inside the opening of stage main section 92, a magnetic pole unit, which is similar to the magnetic pole unit on the wafer stage WST side (stage main section 91 side), is arranged. This magnetic pole unit and X-axis stator 80 constitute a moving magnet type X-axis linear motor that drives measurement stage MST in the X-axis direction.

In the embodiment, each of the linear motors described above that constitute stage drive system 124 is controlled by main controller 20 shown in FIG. 6. Incidentally, each linear motor is not limited to either one of the moving magnet type or the moving coil type, and the types can appropriately be selected as needed.

Incidentally, by making thrust forces severally generated by a pair of Y-axis linear motors 84 and 85 be slightly different, a yawing amount (rotation quantity in the θ_z direction) of wafer stage WST can be controlled. Further, by making thrust forces severally generated by a pair of Y-axis linear motors 82 and 83 be slightly different, a yawing amount of measurement stage MST can be controlled.

Wafer stage WST includes stage main section 91 previously described and a wafer table WTB that is mounted on stage main section 91. Wafer table WTB and stage main section 91 are finely driven relative to base board 12 and X-axis stator 81 in the Z-axis direction, the θ_x direction, and the θ_y direction by a Z leveling mechanism (not shown) (including, for example, a voice coil motor and the like). More specifically, wafer table WTB is finely movable in the Z-axis direction and can also be inclined (tilted) with respect to the XY plane (or the image plane of projection optical system PL). Incidentally, in FIG. 6, stage drive system 124 is shown including each of the linear motors and the Z-leveling mechanism described above. Further, wafer table WTB can also be configured finely movable in at least one of the X-axis, the Y-axis, and the θ_z directions.

On wafer table WTB, a wafer holder (not shown) that holds wafer W by vacuum suction or the like is arranged. The wafer holder may also be formed integrally with wafer table WTB, but in the embodiment, the wafer holder and wafer table WTB are separately configured, and the wafer holder is fixed inside a recessed portion of wafer table WTB, for example, by vacuum suction or the like. Further, on the upper surface of wafer table WTB, a plate (liquid repellent plate) 28 is arranged, which has the surface (liquid repellent surface) substantially flush with the surface of a wafer mounted on the wafer holder to which liquid repellent processing with respect to liquid Lq is performed, has a rectangular outer shape (contour), and has a circular opening that is formed in the center portion and is slightly larger than the wafer

holder (a mounting area of the wafer). Plate 28 is made of materials with a low coefficient of thermal expansion, such as glasses or ceramics (such as Zerodur (the brand name) of Schott AG, Al_2O_3 , or TiC), and on the surface of plate 28, a liquid repellent film is formed by, for example, fluorine resin materials, fluorine series resin materials such as polytetrafluoroethylene (Teflon (registered trademark)), acrylic resin materials, or silicon series resin materials. Further, as shown in a plan view of wafer table WTB (wafer stage WST) in FIG. 4A, plate 28 has a first liquid repellent area 28a whose outer shape (contour) is rectangular enclosing a circular opening, and a second liquid repellent area 28b that has a rectangular frame (annular) shape placed around the first liquid repellent area 28a. On the first liquid repellent area 28a, for example, at the time of an exposure operation, at least a part of a liquid immersion area 14 that is protruded from the surface of the wafer is formed, and on the second liquid repellent area 28b, scales (grating section) for an encoder system (to be described later) are formed. Incidentally, at least a part of the surface of plate 28 does not have to be flush with the surface of the wafer, that is, may have a different height from that of the surface of the wafer. Further, plate 28 may be a single plate, but in the embodiment, plate 28 is configured by combining a plurality of plates, for example, first and second liquid repellent plates that correspond to the first liquid repellent area 28a and the second liquid repellent area 28b respectively. In the embodiment, pure water is used as liquid Lq as is described above, and therefore, hereinafter the first liquid repellent

area 28a and the second liquid repellent area 28b are also referred to as a first water repellent plate 28a and a second water repellent plate 28b.

In this case, exposure light IL is irradiated to the
5 first water repellent plate 28a on the inner side, while exposure light IL is hardly irradiated to the second water repellent plate 28b on the outer side. Taking this fact into consideration, in the embodiment, a first water repellent area to which water repellent coat having sufficient resistance
10 to exposure light IL (light in a vacuum ultraviolet region, in this case) is applied is formed on the surface of the first water repellent plate 28a, and a second water repellent area to which water repellent coat having resistance to exposure light IL inferior to the first water repellent area is applied
15 is formed on the surface of the second water repellent plate 28b. In general, since it is difficult to apply water repellent coat having sufficient resistance to exposure light IL (light in a vacuum ultraviolet region, in this case) to a glass plate, it is effective to separate the water repellent
20 plate into two sections in this manner, i.e. the first water repellent plate 28a and the second water repellent plate 28b around it. Incidentally, the present invention is not limited to this, and two types of water repellent coat that have different resistance to exposure light IL may also be applied
25 on the upper surface of the same plate in order to form the first water repellent area and the second water repellent area. Further, the same kind of water repellent coat may be applied to the first and second water repellent areas. For example, only one water repellent area may also be formed on the same

plate.

Further, as is obvious from FIG. 4A, at the end portion on the +Y side of the first water repellent plate 28a, a rectangular cutout is formed in the center portion in the X-axis direction, and a measurement plate 30 is embedded inside the rectangular space (inside the cutout) that is enclosed by the cutout and the second water repellent plate 28b. A fiducial mark FM is formed in the center in the longitudinal direction of measurement plate 30 (on a centerline LL of wafer table WTB), and a pair of aerial image measurement slit patterns SL are formed in a symmetrical placement with respect to the center of fiducial mark FM on one side and the other side in the X-axis direction of fiducial mark FM. As each of aerial image measurement slit patterns SL, an L-shaped slit pattern having sides along the Y-axis direction and X-axis direction can be used, as an example.

Further, as shown in FIG. 4B, at the wafer stage WST section below each of aerial image measurement slit patterns SL, an L-shaped housing 36 in which an optical system containing an objective lens, a mirror, a relay lens and the like is housed is attached in a partially embedded state penetrating through a part of the inside of wafer table WTB and stage main section 91. Housing 36 is arranged in pairs corresponding to the pair of aerial image measurement slit patterns SL, although omitted in the drawing.

The optical system inside housing 36 guides illumination light IL that has been transmitted through aerial image measurement slit pattern SL downward from above along an L-shaped route and emits the light toward the -Y-direction.

Incidentally, in the following description, the optical system inside housing 36 is described as a light-transmitting system 36 by using the same reference code as housing 36 for the sake of convenience.

5 Moreover, on the upper surface of the second water repellent plate 28b, multiple grid lines are directly formed in a predetermine pitch along each of four sides. More specifically, in areas on one side and the other side in the X-axis direction of the second water repellent plate 28b (both
10 sides in the horizontal direction in FIG. 4A), Y scales 39Y₁ and 39Y₂ are formed, respectively. Y scales 39Y₁ and 39Y₂ are each composed of, for example, a reflective grating (e.g. diffraction grating) having a periodic direction in the Y-axis direction in which grid lines 38 having the longitudinal
15 direction in the X-axis direction are formed in a predetermined pitch along a direction parallel to the Y-axis (Y-axis direction).

 Similarly, in areas on one side and the other side in the Y-axis direction of the second water repellent plate 28b
20 (both sides in the vertical direction in FIG. 4A), X scales 39X₁ and 39X₂ are formed respectively. X scales 39X₁ and 39X₂ are each composed of, for example, a reflective grating (e.g. diffraction grating) having a periodic direction in the X-axis direction in which grid lines 37 having the longitudinal
25 direction in the Y-axis direction are formed in a predetermined pitch along a direction parallel to the X-axis (X-axis direction). As each of the scales, the scale made up of a reflective diffraction grating RG (refer to FIG. 8) that is created by, for example, hologram or the like on the surface

of the second water repellent plate 28b is used. In this case, each scale has gratings made up of narrow slits, grooves or the like that are marked at a predetermined distance (pitch) as graduations. The type of diffraction grating used for each
5 scale is not limited, and not only the diffraction grating made up of grooves or the like that are mechanically formed, but also, for example, the diffraction grating that is created by exposing interference fringe on a photosensitive resin may be used. However, each scale is created by marking the
10 graduations of the diffraction grating, for example, in a pitch between 138nm to 4 μ m, for example, a pitch of 1 μ m on a thin plate shaped glass. These scales are covered with the liquid repellent film (water repellent film) described above. Incidentally, the pitch of the grating is shown much wider
15 in FIG. 4A than the actual pitch, for the sake of convenience. The same is true also in other drawings.

In this manner, in the embodiment, since the second water repellent plate 28b itself constitutes the scales, a glass plate with low-thermal expansion is to be used as the second
20 water repellent plate 28b. However, the present invention is not limited to this, and a scale member made up of a glass plate or the like with low-thermal expansion on which a grating is formed may also be fixed on the upper surface of wafer table WTB, by a plate spring (or vacuum suction) or the like so as
25 to prevent local shrinkage/expansion. In this case, a water repellent plate to which the same water repellent coat is applied on the entire surface may be used instead of plate 28. Or, wafer table WTB may also be formed by a low thermal expansion material, and in such a case, a pair of Y scales

and a pair of X scales may be directly formed on the upper surface of wafer table WTB.

Incidentally, in order to protect the diffraction grating, it is also effective to cover the grating with a glass plate with a coefficient of low thermal expansion that has liquid repellency. In this case, the thickness of the glass plate, for example, is 1mm, and the glass plate is set on the upper surface of the wafer table WST so that its surface is at the same height as the wafer surface. Therefore, the distance between the surface (substantially flush with the upper surface of wafer stage WST in the embodiment) of wafer W held (mounted) on wafer stage WST and the grating surface of the scale in the Z-axis direction is to be 1mm.

Incidentally, a lay out pattern is arranged for deciding the relative position between an encoder head and a scale near the edge of the scale (to be described later). The lay out pattern is configured from grid lines that have different reflectivity, and when the encoder head scans the pattern, the intensity of the output signal of the encoder changes. Therefore, a threshold value is determined beforehand, and the position where the intensity of the output signal exceeds the threshold value is detected. Then, the relative position between the encoder head and the scale is set, with the detected position as a reference.

In the embodiment, main controller 20 can obtain the displacement of wafer stage WST in directions of six degrees of freedom (the Z, X, Y, θ_z , θ_x , and θ_y directions) in the entire stroke area from the measurement results of interferometer system 118 (refer to FIG. 6). In this case,

interferometer system 118 includes X interferometers 126 to 128, Y interferometer 16, and Z interferometers 43A and 43B.

To the -Y edge surface and the -X edge surface of wafer table WTB, mirror-polishing is applied, respectively, and a
5 reflection surface 17a and a reflection surface 17b shown in FIG. 2 are formed. By severally irradiating an interferometer beam (measurement beam) to reflection surface 17a and reflection surface 17b and receiving a reflected light of each beam, Y interferometer 16 and X interferometers 126, 127, and
10 128 (X interferometers 126 to 128 are not shown in FIG. 1, refer to FIG. 2) that constitutes a part of interferometer system 118 (refer to FIG. 6) measure a displacement of each reflection surface from a datum position (generally, a fixed mirror is placed on the side surface of projection unit PU,
15 and the surface is used as a reference surface), that is, positional information of wafer stage WST within the XY plane, and positional information that has been measured is supplied to main controller 20. In the embodiment, as it will be described later on, as each interferometer, a multiaxial
20 interferometer that has a plurality of measurement axes is used with an exception for a part of the interferometers.

Meanwhile, to the side surface on the -Y side of stage main section 91, a movable mirror 41 having the longitudinal direction in the X-axis direction is attached via a kinematic
25 support mechanism (not shown), as shown in FIGS. 1 and 4B.

A pair of Z interferometers 43A and 43B (refer to FIGS. 1 and 2) that configures a part of interferometer system 118 (refer to FIG. 6) and irradiates measurement beams on movable mirror 41 is arranged facing movable mirror 41. To be more

specific, as it can be seen when viewing FIGS. 2 and 4B together, movable mirror 41 is designed so that the length in the X-axis direction is longer than reflection surface 17a of wafer table WTB by at least the interval of Z interferometers 43A and 43B.

5 Further, movable mirror 41 is composed of a member having a hexagonal cross-section shape as in a rectangle and an isosceles trapezoid that have been integrated.

Mirror-polishing is applied to the surface on the -Y side of movable mirror 41, and three reflection surfaces 41b, 41a, and 41c are formed.

Reflection surface 41a configures the edge surface on the -Y side of movable mirror 41, and reflection surface 41a is parallel to the XZ plane and also extends in the X-axis direction. Reflection surface 41b configures a surface
15 adjacent to the +Z side of reflection surface 41a, and reflection surface 41b is parallel with a plane inclined in a clockwise direction in FIG. 4B at a predetermined angle with respect to the XZ plane and also extends in the X-axis direction. Reflection surface 41c configures a surface adjacent to the
20 -Z side of reflection surface 41a, and is arranged symmetrically with reflection surface 41b, with reflection surface 41a in between.

As it can be seen when viewing FIGS. 1 and 2 together, Z interferometers 43A and 43B are placed apart on one side
25 and the other side of Y interferometer 16 in the X-axis direction at a substantially equal distance and at positions slightly lower than Y interferometer 16, respectively.

From each of the Z interferometers 43A and 43B, as shown in FIG. 1, a measurement beam B1 along the Y-axis direction

is irradiated toward reflection surface 41b, and a measurement beam B2 along the Y-axis direction is irradiated toward reflection surface 41c (refer to FIG. 4B). In the embodiment, a fixed mirror 47A having a reflection surface orthogonal to measurement beam B1 reflected off reflection surface 41b and a fixed mirror 47B having a reflection surface orthogonal to measurement beam B2 reflected off reflection surface 41c are arranged, each extending in the X-axis direction at a position distanced apart from movable mirror 41 in the - Y-direction by a predetermined distance in a state where the fixed mirrors do not interfere with measurement beams B1 and B2.

Fixed mirrors 47A and 47B are supported, for example, by the same support body (not shown) arranged in the frame (not shown) which supports projection unit PU. Incidentally, fixed mirrors 47A and 47B can be arranged in the measurement frame or the like previously described. Further, in the embodiment, movable mirror 41 having three reflection surfaces 41b, 41a, and 41c and fixed mirrors 47A and 47B were arranged, however, the present invention is not limited to this, and for example, a configuration in which a movable mirror having an inclined surface of 45 degrees is arranged on the side surface of stage main section 91 and a fixed mirror is placed above wafer stage WST can be employed. In this case, the fixed mirror can be arranged in the support body previously described or in the measurement frame.

Y interferometer 16, as shown in FIG. 2, irradiates measurement beams $B4_1$ and $B4_2$ on reflection surface 17a of wafer table WTB along measurement axes in the Y-axis direction spaced apart by an equal distance to the -X side and the +X side from

a straight line that is parallel to the Y-axis which passes through the projection center (optical axis AX, refer to FIG. 1) of projection optical system PL, and by receiving each reflected light, detects the position of wafer table WTB in the Y-axis direction (a Y position) at the irradiation point of measurement beams B4₁ and B4₂. Incidentally, in FIG. 1, measurement beams B4₁ and B4₂ are representatively shown as measurement beam B4.

Further, Y interferometer 16 irradiates a measurement beam B3 toward reflection surface 41a along a measurement axis in the Y-axis direction with a predetermined distance in the Z-axis direction spaced between measurement beams B4₁ and B4₂, and by receiving measurement beam B3 reflected off reflection surface 41a, detects the Y position of reflection surface 41a (more specifically wafer stage WST) of movable mirror 41.

Main controller 20 computes the Y position (or to be more precise, displacement ΔY in the Y-axis direction) of reflection surface 17a, or more specifically, wafer table WTB (wafer stage WST), based on an average value of the measurement values of the measurement axes corresponding to measurement beams B4₁ and B4₂ of Y interferometer 16. Further, main controller 20 computes displacement (yawing amount) $\Delta\theta_z^{(Y)}$ in the rotational direction around the Z-axis (the θ_z direction) of wafer table WTB, based on a difference of the measurement values of the measurement axes corresponding to measurement beams B4₁ and B4₂. Further, main controller 20 computes displacement (pitching amount) $\Delta\theta_x$ in the θ_x direction of wafer stage WST, based on the Y position (displacement ΔY in the Y-axis direction) in reflection surface 17a and reflection

surface 41a.

Further, as shown in FIG. 2, X interferometer 126 irradiates measurement beams B5₁ and B5₂ on wafer table WTB along the dual measurement axes spaced apart from straight line LH in the X-axis direction that passes the optical axis of projection optical system PL by the same distance, and based on the measurement values of the measurement axes corresponding to measurement beams B5₁ and B5₂, main controller 20 computes a position (an X position, or to be more precise, displacement ΔX in the X-axis direction) of wafer table WTB in the X-axis direction. Further, main controller 20 computes displacement (yawing amount) $\Delta \theta z^{(x)}$ of wafer table WTB in the θz direction from a difference of the measurement values of the measurement axes corresponding to measurement beams B5₁ and B5₂. Incidentally, $\Delta \theta z^{(x)}$ obtained from X interferometer 126 and $\Delta \theta z^{(y)}$ obtained from Y interferometer 16 are equal to each other, and represents displacement (yawing amount) $\Delta \theta z$ of wafer table WTB in the θz direction.

Further, as is indicated in a dotted line in FIG. 2, a measurement beam B7 is emitted from X interferometer 128 along a measurement axis parallel to the X-axis. X interferometer 128 actually irradiates measurement beam B7 on reflection surface 17b of wafer table WTB located in the vicinity of an unloading position UP and a loading position LP along a measurement axis, which is parallel to the X-axis and joins unloading position UP and loading position LP (refer to FIG. 3) as in the description later on. Further, as shown in FIG. 2, a measurement beam B6 from X interferometer 127 is irradiated on reflection surface 17b of wafer table WTB.

Measurement beam B6 is actually irradiated on reflection surface 17b of wafer table WTB along a measurement axis parallel to the X-axis that passes through the detection center of a primary alignment system AL1.

5 Main controller 20 can obtain displacement ΔX of wafer table WTB in the X-axis direction also from the measurement values of measurement beam B6 of X interferometer 127 and the measurement values of measurement beam B7 of X interferometer 128. However, the three X interferometers 126, 127, and 128
10 are placed differently regarding the Y-axis direction, and X interferometer 126 is used at the time of exposure as shown in FIG. 22, X interferometer 127 is used at the time of wafer alignment as shown in FIG. 29 and the like, and X interferometer 128 is used at the time of wafer loading shown in FIGS. 26
15 and 27 and wafer unloading shown in FIG. 25.

 Further from Z interferometers 43A and 43B, measurement beams B1 and B2 that proceed along the Y-axis are irradiated toward movable mirror 41, respectively. These measurement beams B1 and B2 are incident on reflection surfaces 41b and
20 41c of movable mirror 41, respectively, at a predetermined angle of incidence (the angle is to be $\theta/2$). Then, measurement beams B1 and B2 are reflected off reflection surfaces 41b and 41c, respectively, and are incident on the reflection surfaces of fixed mirrors 47A and 47B perpendicularly. Then,
25 measurement beams B1 and B2, which were reflected off the reflection surface of fixed mirrors 47A and 47B, are reflected off reflection surfaces 41b and 41c again (return the optical path at the time of incidence), respectively, and are received by Z interferometers 43A and 43B.

In this case, when displacement of wafer stage WST (more specifically movable mirror 41) in the Y-axis direction is ΔY_o and displacement in the Z-axis direction is ΔZ_o , an optical path length change ΔL_1 of measurement beam B1 and an optical path length change ΔL_2 of measurement beam B2 received at of Z interferometers 43A and 43B can respectively be expressed as in formulas (1) and (2) below.

$$\Delta L_1 = \Delta Y_o \times (1 + \cos\theta) - \Delta Z_o \times \sin\theta \dots (1)$$

$$\Delta L_2 = \Delta Y_o \times (1 + \cos\theta) + \Delta Z_o \times \sin\theta \dots (2)$$

Accordingly, from formulas (1) and (2), ΔZ_o and ΔY_o can be obtained using the following formulas (3) and (4).

$$\Delta Z_o = (\Delta L_2 - \Delta L_1) / 2\sin\theta \dots (3)$$

$$\Delta Y_o = (\Delta L_1 + \Delta L_2) / \{2(1 + \cos\theta)\} \dots (4)$$

Displacements ΔZ_o and ΔY_o above can be obtained with Z interferometers 43A and 43B respectively. Therefore, displacement which is obtained using Z interferometer 43A is to be ΔZ_oR and ΔY_oR , and displacement which is obtained using Z interferometer 43B is to be ΔZ_oL and ΔY_oL . And the distance between measurement beams B1 and B2 irradiated by Z interferometers 43A and 43B, respectively, in the X-axis direction is to be a distance D (refer to FIG. 2). Under such premises, displacement (yawing amount) $\Delta\theta_z$ of movable mirror 41 (more specifically wafer stage WST) in the θ_z direction and displacement (rolling amount) $\Delta\theta_y$ of movable mirror 41 (more specifically wafer stage WST) in the θ_y direction can

be obtained by the following formulas (5) and (6).

$$\Delta\theta_z \approx (\Delta Y_{oR} - \Delta Y_{oL}) / D \dots (5)$$

$$\Delta\theta_y \approx (\Delta Z_{oL} - \Delta Z_{oR}) / D \dots (6)$$

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Accordingly, by using the formulas (3) to (6) above, main controller 20 can compute displacement of wafer stage WST in four degrees of freedom, ΔZ_o , ΔY_o , $\Delta\theta_z$, and $\Delta\theta_y$, based on the measurement results of Z interferometers 43A and 43B.

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In the manner described above, from the measurement results of interferometer system 118, main controller 20 can obtain displacement of wafer stage WST in directions of six degrees of freedom (Z, X, Y, θ_z , θ_x , and θ_y directions). Incidentally, in the embodiment, interferometer system 118 could measure the positional information of wafer stage WST in directions of six degrees of freedom, however, the measurement direction is not limited to directions of six degrees of freedom, and the measurement direction can be directions of five degrees of freedom or less.

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Incidentally, in the embodiment, the case has been described where wafer stage WST (91, WTB) is a single stage that can move in six degrees of freedom, however, the present invention is not limited to this, and wafer stage WST can be configured including stage main section 91 which can move freely in the XY plane, and wafer table WTB mounted on stage main section 91 that can be finely driven relative to stage main section 91 at least in the Z-axis direction, the θ_x direction, and the θ_y direction. In this case, movable mirror 41 described earlier is arranged in wafer table WTB. Further,

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instead of reflection surface 17a and reflection surface 17b, a movable mirror consisting of a plane mirror can be arranged in wafer table WTB.

However, in the embodiment, positional information
5 (positional information in directions of three degrees of freedom including rotary information in the θz direction) of wafer stage WST (wafer table WTB) in the XY plane is mainly measured by an encoder system described later on, and the measurement values of interferometer 16, 126, and 127 are used
10 secondarily as backup or the like, such as in the case of correcting (calibrating) a long-term change (due to, for example, temporal deformation of a scale) of the measurement values of the encoder system, or in the case of output abnormality in the encoder. Incidentally, in the embodiment,
15 of the positional information of wafer stage WST in directions of six degrees of freedom, positional information in directions of three degrees of freedom including the X-axis direction, the Y-axis direction and the θz direction is measured by the encoder system described later on, and
20 positional information of the remaining directions of three degrees of freedom, or more specifically, the positional information in the Z-axis direction, the θx direction, and the θy direction is measured by a measurement system which will also be described later that has a plurality of Z sensors.
25 In this case, positional information of the remaining directions of three degrees of freedom can be measured by both the measurement system and interferometer system 118. For example, positional information in the Z-axis direction and the θy direction can be measured by the measurement system,

and positional information in the θx direction can be measured by interferometer system 118.

Incidentally, at least a part of interferometer system 118 (such as an optical system) may be arranged at the main frame that holds projection unit PU, or may also be arranged integrally with projection unit PU that is supported in a suspended state as is described above, however, in the embodiment, interferometer system 118 is to be arranged at the measurement frame described above.

Measurement stage MST includes stage main section 92 previously described, and measurement table MTB mounted on stage main section 92. Measurement table MTB is mounted on stage main section 92, via the Z leveling mechanism (not shown). However, the present invention is not limited to this, and for example, measurement stage MST can employ the so-called coarse and fine movement structure in which measurement table MTB can be finely driven in the X-axis direction, the Y-axis direction, and the θz direction with respect to stage main section 92, or measurement table MTB can be fixed to stage main section 92, and all of measurement stage MST including measurement table MTB and stage main section 92 can be configured drivable in directions of six degrees of freedom.

Various measurement members are arranged at measurement table MTB (and stage main section 92). As such measurement members, for example, as shown in FIGS. 2 and 5A, members such as an irregular illuminance sensor 94 that has a pinhole-shaped light-receiving section which receives illumination light IL on an image plane of projection optical system PL, an aerial image measuring instrument 96 that measures an aerial image

(projected image) of a pattern projected by projection optical system PL, a wavefront aberration measuring instrument 98 by the Shack-Hartman method that is disclosed in, for example, the pamphlet of International Publication No. WO 03/065428 and the like are employed. As wavefront aberration measuring instrument 98, the one disclosed in, for example, the pamphlet of International Publication No. WO 99/60361 (the corresponding EP Patent Application Publication No. 1 079 223) can also be used.

10 As uneven illuminance measuring sensor 94, the configuration similar to the one that is disclosed in, for example, Kokai (Japanese Unexamined Patent Application Publication) No. 57-117238 (the corresponding U.S. Patent No. 4,465,368) and the like can be used. Further, as aerial image measuring instrument 96, the configuration similar to the one that is disclosed in, for example, Kokai (Japanese Unexamined Patent Application Publication) No. 2002-014005 (the corresponding U.S. Patent Application Publication No. 2002/0041377) and the like can be used. Incidentally, three measurement members (94, 96 and 98) are to be arranged at measurement stage MST in the embodiment, however, the types and/or the number of measurement members are/is not limited to them. As the measurement members, for example, measurement members such as a transmittance measuring instrument that measures a transmittance of projection optical system PL, and/or a measuring instrument that observes local liquid immersion device 8, for example, nozzle unit 32 (or tip lens 191) or the like may also be used. Furthermore, members different from the measurement members such as a cleaning

member that cleans nozzle unit 32, tip lens 191 or the like may also be mounted on measurement stage MST.

In the embodiment, as it can be seen from FIG. 5A, the sensors that are frequently used such as uneven illuminance measuring sensor 94 and aerial image measuring instrument 96 are placed on a centerline CL (Y-axis passing through the center) of measurement stage MST. Therefore, in the embodiment, measurement using these sensors can be performed by moving measurement stage MST only in the Y-axis direction without moving the measurement stage in the X-axis direction.

In addition to each of the sensors described above, an illuminance monitor that has a light-receiving section having a predetermined area size that receives illumination light IL on the image plane of projection optical system PL may also be employed, which is disclosed in, for example, Kokai (Japanese Unexamined Patent Application Publication) No. 11-016816 (the corresponding U.S. Patent Application Publication No. 2002/0061469) and the like. The illuminance monitor is also preferably placed on the centerline.

Incidentally, in the embodiment, liquid immersion exposure is performed in which wafer W is exposed with exposure light (illumination light) IL via projection optical system PL and liquid (water) Lq, and accordingly uneven illuminance measuring sensor 94 (and the illuminance monitor), aerial image measuring instrument 96 and wavefront aberration measuring instrument 98 that are used in measurement using illumination light IL receive illumination light IL via projection optical system PL and water Lq. Further, only a part of each sensor such as the optical system may be mounted

on measurement table MTB (and stage main section 92), or the entire sensor may be placed on measurement table MTB (and stage main section 92).

As shown in FIG. 5B, a frame-shaped attachment member 42 is fixed to the end surface on the -Y side of stage main section 92 of measurement stage MST. Further, to the end surface on the -Y side of stage main section 92, a pair of photodetection systems 44 are fixed in the vicinity of the center position in the X-axis direction inside an opening of attachment member 42, in the placement capable of facing a pair of light-transmitting systems 36 described previously. Each of photodetection systems 44 is composed of an optical system such as a relay lens, a light receiving element such as a photomultiplier tube, and a housing that houses them. As it can be easily imagined from FIGS. 4B and 5B and the description so far, in the embodiment, in a state where wafer stage WST and measurement stage MST are closer together within a predetermined distance in the Y-axis direction (including a contact state), illumination light IL that has been transmitted through each aerial image measurement slit pattern SL of measurement plate 30 is guided by each light-transmitting system 36 and received by the light-receiving element inside each photodetection system 44. That is, measurement plate 30, light-transmitting systems 36 and photodetection systems 44 constitute an aerial image measuring 45 (refer to FIG. 6), which is similar to the one disclosed in Kokai (Japanese Unexamined Patent Application Publication) No. 2002-014005 (the corresponding U.S. Patent Application Publication No. 2002/0041377) referred to

previously, and the like.

On attachment member 42, a confidential bar (hereinafter, shortly referred to as a "CD bar") 46 that is made up of a bar-shaped member having a rectangular sectional shape and serves as a reference member is arranged extending in the X-axis direction. CD bar 46 is kinematically supported on measurement stage MST by a full-kinematic mount structure.

Since CD bar 46 serves as a prototype standard (measurement standard), optical glass ceramics with a low coefficient of thermal expansion, such as Zerodur (the brand name) of Schott AG are employed as the materials. The flatness degree of the upper surface (the surface) of CD bar 46 is set high to be around the same level as a so-called datum plane plate. Further, as shown in FIG. 5A, a reference grating (e.g. diffraction grating) 52 whose periodic direction is in the Y-axis direction is respectively formed in the vicinity of the end portions on one side and the other side in the longitudinal direction of CD bar 46. The pair of reference gratings 52 is formed placed apart from each other at a predetermined distance (which is to be "L") in the symmetrical placement with respect to the center in the X-axis direction of CD bar 46, that is, centerline CL described above.

Further, on the upper surface of CD bar 46, a plurality of reference marks M are formed in the placement as shown in FIG. 5A. The plurality of reference marks M are formed in three-row arrays in the Y-axis direction in the same pitch, and the array of each row is formed being shifted from each other by a predetermined distance in the X-axis direction. As each of reference marks M, a two-dimensional mark having

a size that can be detected by a primary alignment system and secondary alignment systems (to be described later) is used. Reference mark M may also be different in shape (constitution) from fiducial mark FM described previously, but in the
5 embodiment, reference mark M and fiducial mark FM have the same constitution and also they have the same constitution with that of an alignment mark of wafer W. Incidentally, in the embodiment, the surface of CD bar 46 and the surface of measurement table MTB (which may include the measurement
10 members described above) are also covered with a liquid repellent film (water repellent film) severally.

Also on the +Y end surface and the -X end surface of measurement table MTB, reflection surfaces 19a and 19b are formed similar to wafer table WTB as is described above (refer
15 to FIGS. 2 and 5A). By irradiating an interferometer beam (measurement beam), as shown in FIG. 2, on reflection surfaces 19a and 19b and receiving a reflected light of each interferometer beam, a Y interferometer 18 and an X
interferometer 130 (X interferometer 130 is not shown in FIG. 20 1, refer to FIG. 2) of interferometer system 118 (refer to FIG. 6) measure a displacement of each reflection surface from a datum position, that is, positional information of measurement stage MST (e.g. including at least positional
information in the X-axis and Y-axis directions and rotation
25 information in the θ_z direction), and the measurement values are supplied to main controller 20.

In exposure apparatus 100 of the embodiment, in actuality, a primary alignment system AL1 is placed on straight line LV passing through the center of projection unit PU

PU (optical axis AX of projection optical system PL, which also coincides with the center of exposure area IA in the embodiment) and being parallel to the Y-axis, and has a detection center at a position that is spaced apart from the optical axis at a predetermined distance on the -Y side as shown in FIG. 3, although omitted in FIG. 1 from the viewpoint of avoiding intricacy of the drawing. Primary alignment system AL1 is fixed to the lower surface of a main frame (not shown) via a support member 54. On one side and the other side in the X-axis direction with primary alignment system AL1 in between, secondary alignment systems AL2₁ and AL2₂, and AL2₃ and AL2₄ whose detection centers are substantially symmetrically placed with respect to straight line LV are severally arranged. That is, five alignment systems AL1 and AL2₁ to AL2₄ are placed so that their detection centers are placed at different positions in the X-axis direction, that is, placed along the X-axis direction.

As is representatively shown by secondary alignment system AL2₄, each secondary alignment system AL2_n (n=1 to 4) is fixed to a tip (turning end) of an arm 56_n (n=1 to 4) that can turn around a rotation center O as the center in a predetermined angle range in clockwise and anticlockwise directions in FIG. 3. In the embodiment, a part of each secondary alignment system AL2_n (e.g. including at least an optical system that irradiates an alignment light to a detection area and also leads the light that is generated from a subject mark within the detection area to a light-receiving element) is fixed to arm 56_n and the remaining section is arranged at the main frame that holds projection unit PU. The

X-positions of secondary alignment systems AL2₁, AL2₂, AL2₃ and AL2₄ are severally adjusted by rotating around rotation center O as the center. In other words, the detection areas (or the detection centers) of secondary alignment systems AL2₁, AL2₂, AL2₃ and AL2₄ are independently movable in the X-axis direction. Accordingly, the relative positions of the detection areas of primary alignment system AL1 and secondary alignment systems AL2₁, AL2₂, AL2₃ and AL2₄ are adjustable in the X-axis direction. Incidentally, in the embodiment, the X-positions of secondary alignment systems AL2₁, AL2₂, AL2₃ and AL2₄ are to be adjusted by the rotation of the arms. However, the present invention is not limited to this, and a drive mechanism that drives secondary alignment systems AL2₁, AL2₂, AL2₃ and AL2₄ back and forth in the X-axis direction may also be arranged. Further, at least one of secondary alignment systems AL2₁, AL2₂, AL2₃ and AL2₄ can be moved not only in the X-axis direction but also in the Y-axis direction.

Incidentally, since a part of each secondary alignment system AL2_n is moved by arm 56_n, positional information of the part that is fixed to arm 56_n is measurable by a sensor (not shown) such as, for example, an interferometer or an encoder. The sensor may only measure positional information in the X-axis direction of secondary alignment system AL2_n, or may be capable of measuring positional information in another direction, for example, the Y-axis direction and/or the rotation direction (including at least one of the θ_x and θ_y directions).

On the upper surface of each arm 56_n, a vacuum pad 58_n (n=1 to 4) that is composed of a differential evacuation type air bearing is arranged. Further, arm 56_n is rotated by a

rotation drive mechanism 60_n ($n=1$ to 4 , not shown in FIG. 3, refer to FIG. 6) that includes a motor or the like, in response to instructions of main controller 20. Main controller 20 activates each vacuum pad 58_n to fix each arm 56_n to a main frame (not shown) by suction after rotation adjustment of arm 56_n . Thus, the state of each arm 56_n after rotation angle adjustment, that is, a desired positional relation of four secondary alignment systems $AL2_1$ to $AL2_4$ with respect to primary alignment system $AL1$ is maintained.

10 Incidentally, in the case a portion of the main frame facing arm 56_n is a magnetic body, an electromagnet may also be employed instead of vacuum pad 58.

 In the embodiment, as each of primary alignment system $AL1$ and four secondary alignment systems $AL2_1$ to $AL2_4$, for example, a sensor of an FIA (Field Image Alignment) system by an image processing method is used that irradiates a broadband detection beam that does not expose resist on a wafer to a subject mark, and picks up an image of the subject mark formed on a light-receiving plane by the reflected light from the subject mark and an image of an index (an index pattern on an index plate arranged within each alignment system) (not shown), using an imaging device (such as CCD), and then outputs their imaging signals. The imaging signal from each of primary alignment system $AL1$ and four secondary alignment systems $AL2_1$ to $AL2_4$ is supplied to main controller 20 in FIG. 6.

 Incidentally, each of the alignment systems described above is not limited to the FIA system, and an alignment sensor, which irradiates a coherent detection light to a subject mark

and detects a scattered light or a diffracted light generated from the subject mark or makes two diffracted lights (e.g. diffracted lights of the same order or diffracted lights being diffracted in the same direction) generated from the subject
5 mark interfere and detects an interference light, can naturally be used alone or in combination as needed. Further, five alignment systems AL1 and AL2₁ to AL2₄ are to be arranged in the embodiment. However, the number of alignment systems is not limited to five, but may be the number equal to or more
10 than two and equal to or less than four, or may be the number equal to or more than six, or may be the even number, not the odd number. Moreover, in the embodiment, five alignment systems AL1 and AL2₁ to AL2₄ are to be fixed to the lower surface of the main frame that holds projection unit PU, via support
15 member 54. However, the present invention is not limited to this, and for example, the five alignment systems may also be arranged on the measurement frame described earlier. Further, because alignment systems AL1 and AL2₁ to AL2₄ detect alignment marks on wafer W and reference marks on and CD bar
20 46, in the embodiment, the systems will also be simply referred to as a mark detection system.

In exposure apparatus 100 of the embodiment, as shown in FIG. 3, four head units 62A to 62D of the encoder system are placed in a state of surrounding nozzle unit 32 described
25 earlier, on all four sides. In actual, head units 62A to 62D are fixed to the foregoing main frame that holds projection unit PU in a suspended state via a support member, although omitted in FIG. 3 from the viewpoint of avoiding intricacy of the drawings. Incidentally, for example, in the case

projection unit PU is supported in a suspended state, head units 62A to 62D may be supported in a suspended state integrally with projection unit PU, or may be arranged at the measurement frame described above.

5 Head units 62A and 62C are respectively placed on the +X side and -X side of projection unit PU having the longitudinal direction in the X-axis direction, and are also placed apart at substantially the same distance from optical axis AX of projection optical system PL symmetrically with
10 respect to optical axis AX. Further, head units 62B and 62D are respectively placed on the +Y side and -Y side of projection unit PU having the longitudinal direction in the Y-axis direction and are also placed apart at substantially the same distance from optical axis AX of projection optical system
15 PL.

As shown in FIG. 3, head units 62A and 62C are each equipped with a plurality of (six in this case) Y heads 64 that are placed at a predetermined distance on a straight line LH that passes through optical axis AX of projection optical
20 system PL and is parallel to the X-axis, along the X-axis direction. Head unit 62A constitutes a multiple-lens (six-lens in this case) Y linear encoder (hereinafter, shortly referred to as a "Y encoder" or an "encoder" as needed) 70A (refer to FIG. 6) that measures the position in the Y-axis
25 direction (the Y-position) of wafer stage WST (wafer table WTB) using Y scale 39Y₁ described above. Similarly, head unit 62C constitutes a multiple-lens (six-lens, in this case) Y linear encoder 70C (refer to FIG. 6) that measures the Y-position of wafer stage WST (wafer table WTB) using Y scale

39Y₂ described above. In this case, a distance between adjacent Y heads 64 (i.e. measurement beams) equipped in head units 62A and 62C is set shorter than a width in the X-axis direction of Y scales 39Y₁ and 39Y₂ (to be more accurate, a length of grid line 38). Further, out of a plurality of Y heads 64 that are equipped in each of head units 62A and 62C, Y head 64 located innermost is fixed to the lower end portion of barrel 40 of projection optical system PL (to be more accurate, to the side of nozzle unit 32 enclosing tip lens 191) so as to be placed as close as possible to the optical axis of projection optical system PL.

As shown in FIG. 3, head unit 62B is equipped with a plurality of (seven in this case) X heads 66 that are placed on straight line LV at a predetermined distance along the Y-axis direction. Further, head unit 62D is equipped with a plurality of (eleven in this case, out of eleven X heads, however, three X heads that overlap primary alignment system AL1 are not shown in FIG. 3) X heads 66 that are placed on straight line LV at a predetermined distance. Head unit 62B constitutes a multiple-lens (seven-lens, in this case) X linear encoder (hereinafter, shortly referred to as an "X encoder" or an "encoder" as needed) 70B (refer to FIG. 6) that measures the position in the X-axis direction (the X-position) of wafer stage WST (wafer table WTB) using X scale 39X₁ described above. Further, head unit 62D constitutes a multiple-lens (eleven-lens, in this case) X encoder 70D (refer to FIG. 6) that measures the X-position of wafer stage WST (wafer table WTB) using X scale 39X₂ described above. Further, in the embodiment, for example, at the time of alignment (to

be described later) or the like, two X heads 66 out of eleven X heads 66 that are equipped in head unit 62D simultaneously face X scale 39X₁ and X scale 39X₂ respectively in some cases. In these cases, X scale 39X₁ and X head 66 facing X scale 39X₁ constitute X linear encoder 70B, and X scale 39X₂ and X head 66 facing X scale 39X₂ constitute X linear encoder 70D.

Herein, some of eleven X heads 66, in this case, three X heads are attached to the lower surface side of support member 54 of primary alignment system AL1. Further, a distance between adjacent X heads 66 (measurement beams) that are equipped in each of head units 62B and 62D is set shorter than a width in the Y-axis direction of X scales 39X₁ and 39X₂ (to be more accurate, a length of grid line 37). Further, X head 66 located innermost out of a plurality of X heads 66 that are equipped in each of head units 62B and 62D is fixed to the lower end portion of the barrel of projection optical system PL (to be more accurate, to the side of nozzle unit 32 enclosing tip lens 191) so as to be placed as close as possible to the optical axis of projection optical system PL.

Moreover, on the -X side of secondary alignment system AL2₁ and on the +X side of secondary alignment system AL2₄, Y heads 64y₁ and 64y₂ are respectively arranged, whose detection points are placed on a straight line parallel to the X-axis that passes through the detection center of primary alignment system AL1 and are substantially symmetrically placed with respect to the detection center. The distance between Y heads 64y₁ and 64y₂ is set substantially equal to distance L described previously. Y heads 64y₁ and 64y₂ face Y scales 39Y₂ and 39Y₁ respectively in a state where the center

of wafer W on wafer stage WST is on straight line LV as shown in FIG. 3. On an alignment operation (to be described later) or the like, Y scales 39Y₂ and 39Y₁ are placed facing Y heads 64y₁ and 64y₂ respectively, and the Y-position (and the θ_z rotation) of wafer stage WST is measured by Y heads 64y₁ and 64y₂ (i.e. Y encoders 70C and 70A configured by Y heads 64y₁ and 64y₂).

Further, in the embodiment, at the time of baseline measurement of the secondary alignment systems (to be described later) or the like, a pair of reference gratings 52 of CD bar 46 face Y heads 64y₁ and 64y₂ respectively, and the Y-position of CD bar 46 is measured at the position of each of reference gratings 52 by Y heads 64y₁ and 64y₂ and facing reference gratings 52. In the following description, encoders that are composed of Y heads 64y₁ and 64y₂ facing reference gratings 52 respectively are referred to as Y-axis linear encoders 70E and 70F (refer to FIG. 6).

Six linear encoders 70A to 70F described above measure the positional information of wafer stage WST in each measurement direction at a resolution of, for example, around 0.1 nm, and the measurement values (measurement information) are supplied to main controller 20. Main controller 20 controls the position within the XY plane of wafer table WTB based on the measurement values of linear encoders 70A to 70D, and also controls the rotation in the θ_z direction of CD bar 46 based on the measurement values of linear encoders 70E and 70F. Incidentally, the configuration and the like of the linear encoder will be described further later in the description.

In exposure apparatus 100 of the embodiment, a position measuring device that measures positional information of wafer W in the Z-axis direction is arranged. As shown in FIG. 3, in the embodiment, as the position measuring device, a
5 multipoint focal position detecting system (hereinafter, shortly referred to as a "multipoint AF system") by an oblique incident method is arranged, which is composed of an irradiation system 90a and a photodetection system 90b, and has the configuration similar to the one disclosed in, for
10 example, Kokai (Japanese Unexamined Patent Application Publication) No. 06-283403 (the corresponding U.S. Patent No. 5,448,332) and the like. In the embodiment, as an example, irradiation system 90a is placed on the -Y side of the -X end portion of head unit 62C described previously and
15 photodetection system 90b is placed on the -Y side of the +X end portion of head unit 62A in a state of opposing irradiation system 90a.

A plurality of detection points of the multipoint AF system (90a, 90b) are placed at a predetermined distance along
20 the X-axis direction on the surface to be detected, although it is omitted in the drawings. In the embodiment, the plurality of detection points are placed, for example, in the arrangement of a matrix having one row and M columns (M is a total number of detection points) or having two rows and
25 N columns (N is a half of a total number of detection points). In FIG. 3, the plurality of detection points to which a detection beam is severally irradiated are not individually shown, but are shown as an elongate detection area (beam area) AF that extends in the X-axis direction between irradiation

system 90a and photodetection system 90b. Since the length of detection area AF in the X-axis direction is set to around the same as the diameter of wafer W, positional information (surface position information) in the Z-axis direction across substantially the entire surface of wafer W can be measured by only scanning wafer W in the Y-axis direction once. Further, since detection area AF is placed between liquid immersion area 14 (exposure area 1A) described earlier and the detection areas of the alignment systems (AL1, AL2₁, AL2₂, AL2₃ and AL2₄) in the Y-axis direction, the detection operations of the multipoint AF system and the alignment systems can be performed in parallel. The multipoint AF system may also be arranged on the main frame that holds projection unit PU or the like, but is to be arranged on the measurement frame described earlier in the embodiment.

Incidentally, the plurality of detection points are to be placed in one row and M columns, or two rows and N columns, but the number(s) of rows and/or columns is/are not limited to these numbers. However, in the case the number of rows is two or more, the positions in the X-axis direction of detection points are preferably made to be different even between the different rows. Moreover, the plurality of detection points are to be placed along the X-axis direction. However, the present invention is not limited to this, and all of or some of the plurality of detection points may also be placed at different positions in the Y-axis direction. For example, the plurality of detection points may also be placed along a direction that intersects both of the X-axis and the Y-axis. That is, the positions of the plurality of detection points

only have to be different at least in the X-axis direction. Further, a detection beam is to be irradiated to the plurality of detection points in the embodiment, but a detection beam may also be irradiated to, for example, the entire area of
 5 detection area AF. Furthermore, the length of detection area AF in the X-axis direction does not have to be nearly the same as the diameter of wafer W.

In the embodiment, in the vicinity of detection points located at both ends out of a plurality of detection points
 10 of the multipoint AF system, that is, in the vicinity of both end portions of beam area AF, one each pair of surface position sensors for Z position measurement (hereinafter, shortly referred to as "Z sensors"), that is, a pair of Z sensors 72a and 72b and a pair of Z sensors 72c and 72d are arranged in
 15 the symmetrical placement with respect to straight line LV described earlier. Z sensors 72a to 72d are fixed to the lower surface of a main frame (not shown). As Z sensors 72a to 72d, a sensor that irradiates a light to wafer table WTB from above, receives the reflected light and measures positional
 20 information of the wafer table WTB surface at the irradiation point of the light in the Z-axis direction orthogonal to the XY plane, as an example, an optical displacement sensor (sensor by an optical pickup method), which has the configuration like an optical pickup used in a CD drive device, is used.
 25 Incidentally, Z sensors 72a to 72d may also be arranged on the measurement frame described above or the like.

Moreover, head unit 62C described earlier is equipped with a plurality of (in this case six each, which is a total of twelve) Z sensors $74_{i,j}$ ($i=1, 2, j=1, 2, \dots, 6$), which

are placed corresponding to each other along two straight lines at a predetermined distance, the straight lines being parallel to straight line LH and are located on one side and the other side of straight line LH in the X-axis direction that connects
 5 a plurality of Y heads 64. In this case, Z sensors $74_{1,j}$ and $74_{2,j}$ that make a pair are disposed symmetrical to straight line LH. Furthermore, the plurality of pairs (in this case, six pairs) of Z sensors $74_{1,j}$ and $74_{2,j}$ and a plurality of Y heads 64 are placed alternately in the X-axis direction. As
 10 each Z sensor $74_{1,j}$, a sensor by an optical pickup method similar to Z sensors 72a to 72d described earlier is used.

In this case, the distance between each pair of Z sensors $74_{1,j}$ and $74_{2,j}$ that are located symmetrically with respect to straight line LH is set to be the same distance as the distance
 15 between Z sensors 72a and 72b previously described. Further, a pair of Z sensors $74_{1,4}$ and $74_{2,4}$ are located on the same straight line in the Y-axis direction as with Z sensors 72a and 72b.

Further, head unit 62A described earlier is equipped
 20 with a plurality of (twelve in this case) Z sensors $76_{p,q}$ ($p=1, 2$ and $q=1, 2, \dots, 6$) that are placed symmetrically to a plurality of Z sensors $74_{1,j}$ described earlier with respect to straight line LV described earlier. As each Z sensor $76_{p,q}$, a sensor by an optical pickup method similar to Z sensors 72a
 25 to 72d described earlier is used. Further, a pair of Z sensors $76_{1,3}$ and $76_{2,3}$ are located on the same straight line in the Y-axis direction as with Z sensors 72c and 72d. Incidentally, Z sensors $74_{1,j}$ and $76_{p,q}$ are installed, for example, at the mainframe or the measurement frame previously described.

Further, in the embodiment, the measurement system that has Z sensors 72a to 72d, and 74_{i,j} and 76_{p,q} measures positional information of wafer stage WST in the Z-axis direction using one or a plurality of Z sensors that face the scale previously described. Therefore, in the exposure operation, Z sensors 74_{i,j} and 76_{p,q} used for position measurement are switched, according to the movement of wafer stage WST. Furthermore, in the exposure operation, Y scale 39Y₁ and at least one Z sensor 76_{p,q} face each other, and Y scale 39Y₂ and at least one Z sensor 74_{i,j} also face each other. Accordingly, the measurement system can measure not only positional information of wafer stage WST in the Z-axis direction, but also positional information (rolling) in the θ_y direction. Further, in the embodiment, each Z sensor of the measurement system detects a grating surface (a formation surface of a diffraction grating) of the scale, however, the measurement system can also detect a surface that is different from the grating surface, such as, for example, a surface of the cover glass that covers the grating surface.

Incidentally, in FIG. 3, measurement stage MST is omitted and a liquid immersion area that is formed by water Lq held in the space between measurement stage MST and tip lens 191 is shown by a reference code 14. Further, in FIG. 3, a reference code 78 indicates a local air-conditioning system that blows dry air whose temperature is adjusted to a predetermined temperature to the vicinity of a beam path of the multipoint AF system (90a, 90b) by, for example, downflow as is indicated by outlined arrows in FIG. 3. Further, a reference code UP indicates an unloading position where a

wafer on wafer table WTB is unloaded, and a reference code LP indicates a loading position where a wafer is loaded on wafer table WTB. In the embodiment, unloading position UP and loading position LP are set symmetrically with respect to straight line LV. Incidentally, unloading position UP and loading position LP may be the same position.

FIG. 6 shows the main configuration of the control system of exposure apparatus 100. The control system is mainly configured of main controller 20 composed of a microcomputer (or workstation) that performs overall control of the entire apparatus. In a memory 34 which is an external storage device connecting to main controller 20, correction information, which will be described below, is stored. Incidentally, in FIG. 6, various sensors such as uneven illuminance measuring sensor 94, aerial image measuring instrument 96 and wavefront aberration measuring instrument 98 described previously that are arranged at measurement stage MST are collectively shown as a sensor group 99.

In exposure apparatus 100 of the embodiment which is configured in the manner described above, because the placement of the X scales and Y scales on wafer table WTB and the arrangement of the X heads and Y heads which were described above were employed, in the effective stroke range (more specifically, in the embodiment, the range in which the stage moves for alignment and exposure operation) of wafer stage WST, at least one X head 66 in the total of 18 X heads belonging to head units 62B and 62D must face at least one of X scale $39X_1$ and $39X_2$, and at least one Y head 64 each, or Y head $64y_1$ and $64y_2$ belonging to head units 62A and 62C, also respectively

face Y scales $39Y_1$ and $39Y_2$, respectively, as illustrated in FIGS. 7A and 7B. That is, at least one each of the corresponding heads is made to face at least the three out of the four scales.

5 Incidentally, in FIGS. 7A and 7B, the head which faces the corresponding X scale or Y scale is shown surrounded in a circle.

 Therefore, in the effective stroke range of wafer stage WST referred to earlier, by controlling each motor that
10 configures stage drive system 124, based on at least a total of three measurement values of the encoders, which are encoders 70A and 70C, and at least one of encoders 70B and 70D, main controller 20 can control positional information (including rotation in the θ_z direction) of wafer stage WST in the XY
15 plane with high accuracy. Because the effect of the air fluctuation that the measurement values of encoder 70A to 70D receive is small enough so that it can be ignored when compared with an interferometer, the short-term stability of the measurement values affected by the air fluctuation is
20 remarkably good when compared with the interferometer.

 Further, when wafer stage WST is driven in the X-axis direction as is shown by an outlined arrow in FIG. 7A, Y heads 64 that measure the position of wafer stage WST in the Y-axis direction are sequentially switched, as is indicated by arrows
25 e_1 and e_2 in the drawing, to the adjacent Y heads 64. For example, the heads are switched from Y heads 64_{C3} and 64_{A3} surrounded by a solid circle to Y heads 64_{C4} and 64_{A4} that are surrounded by a dotted circle. Therefore, before or after this switching, a linkage process of the measurement values

which will be described later on is performed. More specifically, in the embodiment, in order to perform the switching of the Y heads 64 and the linkage process of the measurement value smoothly, the distance between adjacent Y heads 64 that head units 62A and 62 have is set smaller than the width of Y scales 39Y₁ and 39Y₂ in the X-axis direction.

Further, in the embodiment, since a distance between adjacent X heads 66 that are equipped in head units 62B and 62D is set narrower than a width of X scales 39X₁ and 39X₂ in the Y-axis direction as is described previously, when wafer stage WST is driven in the Y-axis direction as indicated by an outline arrow in FIG. 7B, X head 66 that measures the position in the X-axis direction of wafer stage WST is sequentially switched to adjacent X head 66 (e.g. X head 66 circled by a solid line is switched to X head 66 circled by a dotted line), and the linkage process of the measurement values is performed before and after the switching.

Next, the configuration and the like of encoders 70A to 70F will be described, focusing on Y encoder 70A that is enlargedly shown in FIG. 8A, as a representative. FIG. 8A shows one Y head 64 of head unit 62A that irradiates a detection light (measurement beam) to Y scale 39Y₁.

Y head 64 is mainly composed of three sections, which are an irradiation system 64a, an optical system 64b and a photodetection system 64c.

Irradiation system 64a includes a light source that emits a laser beam LB in a direction inclined at an angle of 45 degrees with respect to the Y-axis and Z-axis, for example, a semiconductor laser LD, and a converging lens L1 that is

placed on the optical path of laser beam LB emitted from semiconductor laser LD.

Optical system 64b is equipped with a polarization beam splitter PBS whose separation plane is parallel to an XZ plane,
5 a pair of reflection mirrors R1a and R1b, lenses L2a and L2b, quarter wavelength plates (hereinafter, referred to as a $\lambda/4$ plate) WPla and WPlb, reflection mirrors R2a and R2b, and the like.

Photodetection system 64c includes a polarizer
10 (analyzer), a photodetector, and the like.

In Y encoder 70A, laser beam LB emitted from semiconductor laser LD is incident on polarization beam splitter PBS via lens L1, and is split by polarization into two beams LB₁ and LB₂. Beam LB₁ having been transmitted through
15 polarization beam splitter PBS reaches reflective diffraction grating RG that is formed on Y scale 39Y₁, via reflection mirror R1a, and beam LB₂ reflected off polarization beam splitter PBS reaches reflective diffraction grating RG via reflection mirror R1b. Incidentally, "split by polarization" in this
20 case means the splitting of an incident beam into a P-polarization component and an S-polarization component.

Predetermined-order diffraction beams that are generated from diffraction grating RG due to irradiation of beams LB₁ and LB₂, for example, the first-order diffraction
25 beams are severally converted into a circular polarized light by $\lambda/4$ plates WPlb and WPla via lenses L2b and L2a, and reflected by reflection mirrors R2b and R2a and then the beams pass through $\lambda/4$ plates WPlb and WPla again and reach polarization beam splitter PBS by tracing the same optical

path in the reversed direction.

Each of the polarization directions of the two beams that have reached polarization beam splitter PBS is rotated at an angle of 90 degrees with respect to the original direction.

5 Therefore, the first-order diffraction beam of beam LB_1 that was previously transmitted through polarization beam splitter PBS is reflected off polarization beam splitter PBS and is incident on photodetection system 64c, and also the first-order diffraction beam of beam LB_2 that was previously

10 reflected off polarization beam splitter PBS is transmitted through polarization beam splitter PBS and is synthesized concentrically with the first-order diffraction beam of beam LB_1 described earlier and is incident on photodetection system 64c.

15 Then, the polarization directions of the two first-order diffraction beams described above are uniformly arranged by the analyzer inside photodetection system 64c and the beams interfere with each other to be an interference light, and the interference light is detected by the photodetector and

20 is converted into an electric signal in accordance with the intensity of the interference light.

As is obvious from the description above, in Y encoder 70A, since the optical path lengths of the two beams to be interfered are extremely short and also are almost equal to

25 each other, the influence by air fluctuations can mostly be ignored. Then, when Y scale 39Y₁ (more specifically, wafer stage WST) moves in a measurement direction (in this case, the Y-axis direction), the phase of the two beams changes, respectively, which changes the intensity of the interference

light. This change in the intensity of the interference light is detected by photodetection system 64c, and positional information corresponding to the intensity change is output as a measurement value of Y encoder 70A. Other encoders 70B, 70C, 70D, 70E, and 70F are also configured similarly with encoder 70A.

Meanwhile, when wafer stage WST moves in a direction different from the Y-axis direction and a relative motion (a relative motion in a direction besides the measurement direction) occurs between head 64 and Y scale 39Y₁ in a direction besides the direction that should be measured, in most cases, a measurement error occurs in Y encoder 70A due to such motion. Hereinafter, the mechanism of this measurement error generation will be described.

First of all, a relation between the intensity of interference light that is synthesized from two return beams LB₁ and LB₂ and displacement (relative displacement with Y head 64) of Y scale 39Y₂ (reflection grating RG) is derived.

In FIG. 8B, supposing that beam LB₁, which was reflected off reflection mirror R1a, is incident on reflection grating RG at an angle θ_{a0} , and a n_a^{th} order diffraction light is to be generated at an angle θ_{a1} . And the return beam, which is reflected off reflection mirror R2a and follows the return path, is incident on reflection grating RG at an angle θ_{a1} . Then, a diffraction light is generated again. In this case, the diffraction light that occurs at angle θ_{a0} and moves toward reflection mirror R1a following the original optical path is an n_a^{th} order diffraction light, which is a diffraction light of the same order as the diffraction light generated on the

outward path.

Meanwhile, beam LB_2 reflected off reflection mirror R1b is incident on reflection grating RG at an angle θ_{b0} , and an n_b^{th} order diffraction light is generated at an angle θ_{b1} .

5 Supposing that this diffraction light is reflected off reflection mirror R2b and returns to reflection mirror R1b following the same optical path.

In this case, intensity I of the interference light synthesized by the two return beams LB_1 and LB_2 is dependent
10 on a phase difference ϕ between the two return beams LB_1 and LB_2 in the light receiving position of the photodetector, by $I \propto 1 + \cos\phi$. However, the intensity of the two beams LB_1 and LB_2 was to be equal to each other.

Details on deriving phase difference ϕ are omitted here,
15 however, phase difference ϕ is theoretically obtained by the following formula (7).

$$\begin{aligned} \phi = K\Delta L + 4\pi(n_b - n_a) \Delta Y/p \\ + 2K \Delta Z (\cos\theta_{b1} + \cos\theta_{b0} - \cos\theta_{a1} - \cos\theta_{a0}) \dots (7) \end{aligned}$$

20

In this case, $K\Delta L$ is the phase difference due to an optical path difference ΔL of the two beams LB_1 and LB_2 , ΔY is displacement of reflection grating RG in the +Y-direction, ΔZ is displacement of reflection grating RG in the +Z direction,
25 p is the pitch of the diffraction grating, and n_b and n_a are the diffraction order of each diffraction light described above.

Suppose that the encoder is configured so as to satisfy optical path difference $\Delta L = 0$ and a symmetry shown in the

following formula (8).

$$\theta_{a0} = \theta_{b0}, \theta_{a1} = \theta_{b1} \dots (8)$$

5 In such a case, inside the parenthesis of the third term on the right-hand side of formula (7) becomes zero, and also at the same time $n_b = -n_a (=n)$, therefore, the following formula (9) can be obtained.

10 $\phi_{\text{sym}} (\Delta Y) = 2\pi\Delta Y / (p/4n) \dots (9)$

From formula (9) above, it can be seen that phase difference ϕ_{sym} is not dependent on the wavelength of the light.

As a simple example, two cases shown in FIGS. 9A and 9B will now be considered. First of all, in the case of FIG. 9A, an optical axis of head 64 coincides with the Z-axis direction (head 64 is not inclined). Supposing that wafer stage WST was displaced in the Z-axis direction ($\Delta Z \neq 0, \Delta Y = 0$). In this case, because there are no changes in optical path difference ΔL ,
 15 there are no changes in the first term on the right-hand side of formula (7). The second term becomes zero, according to a supposition $\Delta Y = 0$. And, the third term becomes zero because it satisfies the symmetry of formula (8). Accordingly, no change occurs in phase difference ϕ , and further no intensity
 20 change of the interference light occurs. As a result, the measurement value (count value) of the encoder also does not change.

Meanwhile, in the case of FIG. 9B, the optical axis of head 64 is inclined (head 64 is inclined) with respect to the

Z-axis. Supposing that wafer stage WST was displaced in the Z-axis direction from this state ($\Delta Z \neq 0$, $\Delta Y = 0$). In this case as well, because there are no changes in optical path difference ΔL , there are no changes in the first term on the right-hand side of formula (7). And, the second term becomes zero, according to supposition $\Delta Y = 0$. However, because the head is inclined, the symmetry of formula (8) will be lost, and the third term will not become zero and will change in proportion to Z displacement ΔZ . Accordingly, a change occurs in phase difference ϕ , and as a consequence, the measurement value changes. Incidentally, even if head 64 is not gradient, for example, depending on the optical properties (such as telecentricity) of the head, the symmetry of formula (8) is lost, and the measurement value changes likewise. More specifically, characteristic information of the head unit, which is a generation factor of the measurement error of the encoder system, includes not only the gradient of the head but also the optical properties as well.

Further, although it is omitted in the drawings, in the case displacement occurs in a direction perpendicular to the measurement direction (the Y-axis direction) and the optical axis direction (the Z-axis direction), ($\Delta X \neq 0$, $\Delta Y = 0$, $\Delta Z = 0$), the measurement values do not change as long as the direction (longitudinal direction) in which the grid line of diffraction grating RG faces is orthogonal to the measurement direction, however, in the case the direction is not orthogonal, sensitivity occurs with a gain proportional to the angle.

Next, four cases as shown in, for example, FIGS. 10A to 10D, will be considered. First of all, in the case of FIG.

10A, the optical axis of head 64 coincides with the Z-axis direction (head 64 is not inclined). Even if wafer stage WST moves in the +Z direction and shifts to a condition shown in FIG. 10B from this state, the measurement value of the encoder
5 does not change since the case is the same as in FIG. 9A previously described.

Next, suppose that wafer stage WST rotates around the X-axis from the state shown in FIG. 10B and moves into a state shown in FIG. 10C. In this case, although the head and the
10 scale do not perform relative motion, or more specifically, even though $\Delta Y = \Delta Z = 0$, a change occurs in optical path difference ΔL due to the rotation of wafer stage WST, which changes the measurement value of the encoder. That is, a measurement error occurs in the encoder system due to an
15 inclination (tilt) of wafer stage WST.

Next, suppose that wafer stage WST moves downward from a state shown in FIG. 10C and moves into a state shown in FIG. 10D. In this case, a change in optical path difference ΔL does not occur because wafer stage WST does not rotate.
20 However, because the symmetry of formula (8) has been lost, phase difference ϕ changes by Z displacement ΔZ through the third term on the right-hand side of formula (7). Accordingly, the measurement value of the encoder changes. Incidentally, the measurement value of the encoder in the case of FIG. 10D
25 becomes the same measurement value as the case in FIG. 10A.

According to a result of a simulation that the inventors and the like performed, it became clear that the measurement value of the encoder has sensitivity not only to a positional change of the scale in the Y-axis direction, which is the

measurement direction, but also has sensitivity to an attitude change in the θ_x direction (the pitching direction) and the θ_z direction (the yawing direction), and moreover, depends on the positional change in the Z-axis direction in the case
 5 such as when the symmetry has been lost as is previously described. That is, the theoretical description previously described agreed with the result of the simulation.

Therefore, in the embodiment, correction information to correct the measurement error of each encoder caused by the
 10 relative motion of the head and the scale in the direction besides the measurement direction is acquired as follows.

a. First of all, main controller 20 drives wafer stage WST via stage drive system 124, while monitoring the measurement values of Y interferometer 16, X interferometer
 15 126, and Z interferometers 43A and 43B of interferometer system 118, and as shown in FIGS. 11A and 11B, makes Y head 64 located farthest to the -X side of head unit 62A face an arbitrary area (an area circled in FIG. 11A) AR of Y scale 39Y₁ on the upper surface of wafer table WTB.

20 b. Then, based on the measurement values of Y interferometer 16 and Z interferometers 43A and 43B, main controller 20 drives wafer table WTB (wafer stage WST) so that rolling amount θ_y and yawing amount θ_z of wafer table WTB (wafer stage WST) both become zero while a pitching amount θ_x also
 25 becomes a desired value α_0 (in this case, $\alpha_0 = 200\mu\text{rad}$), irradiates a detection light on area AR of Y scale 39Y₁ from head 64 above after the drive, and stores the measurement value which corresponds to a photoelectric conversion signal from head 64 which has received the reflected light in an internal

memory.

c. Next, while maintaining the attitude (pitching amount $\theta_x = \alpha_0$, yawing amount $\theta_z = 0$, rolling amount $\theta_y = 0$) of wafer table WTB (wafer stage WST) based on the measurement values of Y interferometer 16 and Z interferometers 43A and 43B, main controller 20 drives wafer table WTB (wafer stage WST) within a predetermined range, such as, for example, the range of $-100\mu\text{m}$ to $+100\mu\text{m}$ in the Z-axis direction as is indicated by an arrow in FIG. 11B, sequentially takes in the measurement values corresponding to the photoelectric conversion signals from head 64 which has received the reflected light at a predetermined sampling interval while irradiating a detection light on area AR of Y scale 39Y₁ from head 64 described above during the drive, and stores the values in the internal memory.

d. Next, main controller 20 changes the pitching amount of wafer table WTB (wafer stage WST) to $(\theta_x = \alpha_0 - \Delta\alpha)$, based on the measurement values of Y interferometer 16 .

e. Then, as for the attitude after the change, main controller 20 repeats an operation similar to c. described above.

f. Then, main controller 20 alternately repeats the operations of d. and e described above, and for a range where pitching amount θ_x is, for example, $-200\mu\text{rad} < \theta_x < +200\mu\text{rad}$, takes in the measurement values of head 64 within the Z drive range described above at $\Delta\alpha(\text{rad})$, at an interval of, for example, $40\mu\text{rad}$.

g. Next, by plotting each data within the internal memory obtained by the processes b. to e. described above on

a two-dimensional coordinate system whose horizontal axis indicates a Z position and vertical axis indicates an encoder count value, sequentially linking plot points where the pitching amounts are the same, and shifting the horizontal axis in the vertical axis direction so that a line (a horizontal line in the center) which indicates a zero pitching amount passes through the origin, main controller 20 can obtain a graph (a graph that shows a change characteristic of the measurement values of the encoder (head) according to the Z leveling of the wafer stage) like the one shown in FIG. 12.

The values of the vertical axis at each point on the graph in FIG. 12 is none other than the measurement error of the encoder in each Z position, in pitching amount $\theta_x = \alpha$. Therefore, main controller 20 sees pitching amount θ_x , the Z position, and the encoder measurement error at each point on the graph in FIG. 12 as a table data, and stores the table data in memory 34 (refer to FIG. 6) as stage position induced error correction information. Or main controller 20 sees the measurement error as a function of Z position z and pitching amount θ_x , and obtains the function computing an undetermined coefficient, for example, by the least-squares method, and stores the function in memory 34 as stage position induced error correction information.

h. Next, main controller 20 drives wafer stage WST in the - X-direction by a predetermined amount via stage drive system 124 while monitoring the measurement values of X interferometer 126 of interferometer system 118, and as shown in FIG. 13, makes Y head 64 located second from the edge on the -X side of head unit 62A (the Y head next to Y head 64

whose data has already been acquired in the process described above) face area AR previously described (the area circled in FIG. 13) of Y scale 39Y₁ on the upper surface of wafer table WTB.

5 i. Then, main controller 20 performs a process similar to the ones described above on Y head 64, and stores correction information of Y encoder 70A configured by head 64 and Y scale 39Y₁ in memory 34.

 j. Hereinafter, in a similar manner, main controller
10 20 respectively obtains correction information of Y encoder 70A configured by each remaining Y head 64 of head unit 62A and Y scale 39Y₁, correction information of X encoder 70B configured by each X head 66 of head unit 62B and X scale 39X₁, correction information of Y encoder 70C configured by each
15 X head 64 of head unit 62C and Y scale 39Y₂, and correction information of X encoder 70D configured by each X head 66 of head unit 62D and X scale 39X₂, and stores them in memory 34.

 In this case, it is important that the same area on X scale 39X₁ is used on the above-described measurement using
20 each X head 66 of head unit 62B, the same area on Y scale 39Y₂ is used on the above-described measurement using each Y head 64 of head unit 62C, and the same area in X scale 39X₂ is used on the above-described measurement using each Y head 66 of head unit 62D. The reason for this is because if the correction
25 (including the curve correction of reflection surfaces 17a and 17b, and reflection surfaces 41a, 41b, and 41c) of each interferometer of interferometer system 118 has been completed, the attitude of wafer stage WST can be set to a desired attitude anytime based on the measurement values of

the interferometers, and by using the same location of each scale, even if the scale surface is inclined, the measurement error caused by the effect of the inclination does not occur between the heads.

5 Further, main controller 20 performs the measurement described above for Y heads 64y₁ and 64y₂ using the same area on Y scale 39Y₂ and 39Y₁, respectively, which is the same as each Y head 64 of head units 62C and 64A described above, obtains correction information of encoder 70C configured by
10 Y head 64y₁ which faces Y scale 39Y₂ and correction information of encoder 70A configured by Y head 64y₂ which faces Y scale 39Y₁, and stores the information in memory 34.

Next, in a similar procedure as in the case described above where the pitching amount was changed, main controller
15 20 sequentially changes yawing amount θ_z of wafer stage WST for a range of $-200\mu\text{rad} < \theta_z < +200\mu\text{rad}$ and drives wafer table WTB (wafer stage WST) in the Z-axis direction at each position within a predetermined range, such as, for example, within $-100\mu\text{m}$ to $+100\mu\text{m}$, while maintaining both the pitching amount
20 and the rolling amount of wafer stage WST at zero, and during the drive, sequentially takes in the measurement values of the head at a predetermined sampling interval and stores them in the internal memory. Such a measurement is performed for all heads 64 or 66, and in a procedure similar to the one
25 described earlier, by plotting each data within the internal memory on the two-dimensional coordinate system whose horizontal axis indicates the Z position and vertical axis indicates the encoder count value, sequentially linking plot points where the yawing amounts are the same, and shifting

the horizontal axis so that a line (a horizontal line in the center) which indicates a zero yawing amount passes through the origin, main controller 20 can obtain a graph similar to the one shown in FIG. 12. Then, main controller 20 regards
 5 yawing amount θ_z , Z position, and the measurement error at each point on the obtained graph as a table data, and then stores the data in memory 34 as correction information. Or, main controller 20 sees the measurement error as a function of Z position z and yawing amount θ_z , and obtains the function
 10 computing an undetermined coefficient, for example, by the least-squares method, and stores the function in memory 34 as correction information.

In this case, the measurement error of each encoder in the case both the pitching amount and the yawing amount of
 15 wafer stage WST are not zero when wafer stage WST is at Z position z can safely be considered to be a simple sum (a linear sum) of the measurement error that corresponds to the pitching amount described above and the measurement error that corresponds to the yawing amount when wafer stage WST is at
 20 Z position z . The reason for this is, as a result of simulation, it has been confirmed that the measurement error (count value) linearly changes according to the change of the Z position, even when the yawing is changed.

Hereinafter, to simplify the description, a function of
 25 pitching amount θ_x , yawing amount θ_z , and Z position z of wafer stage WST that expresses a measurement error Δy as shown in the next formula (10) is to be obtained for the Y heads of each Y encoder, and to be stored in memory 34. Further, a function of rolling amount θ_y , yawing amount θ_z , and Z

position z of wafer stage WST that expresses a measurement error Δx as shown in the next formula (11) is to be obtained for the X heads of each X encoder, and to be stored in memory 34.

5

$$\Delta y = f(z, \theta_x, \theta_z) = \theta_x (z-a) + \theta_z (z-b) \dots\dots (10)$$

$$\Delta x = g(z, \theta_y, \theta_z) = \theta_y (z-c) + \theta_z (z-d) \dots\dots (11)$$

In formula (10) above, a is a Z -coordinate of a point
 10 where each straight line intersects on the graph in FIG. 12, and b is a Z -coordinate of a point where each straight line intersects on a graph similar to FIG. 12 in the case when the yawing amount is changed so as to acquire the correction information of the Y encoder. Further, in formula (11) above,
 15 c is a Z -coordinate of a point where each straight line intersects on a graph similar to FIG. 12 in the case when the rolling amount is changed so as to acquire the correction information of the X encoder, and d is a Z -coordinate of a point where each straight line intersects on a graph similar
 20 to FIG. 12 in the case when the yawing amount is changed so as to acquire the correction information of the X encoder.

Incidentally, because Δy and Δx described above show the degree of influence of the position of wafer stage WST in the direction besides the measurement direction of the Y encoder or the X encoder (e. g. the θ_x direction or the θ_y direction, the θ_z direction and the Z -axis direction) on the measurement values of the Y encoder or the X encoder, in
 25 the present specification, it will be referred to as a stage position induced error, and because the stage position induced

error can be used as correction information, the correction information is referred to as stage position induced error correction information.

Next, a calibration process of a head position
5 (measurement beam position) for acquiring a position
coordinate of each head (or to be more precise, the measurement
beam emitted from each head) in the XY plane, especially the
position coordinate in the direction besides the measurement
direction, which becomes a premise in processes such as a
10 process to convert the measurement value of an encoder to be
described later into positional information of wafer stage
WST in the XY plane and a linkage process among a plurality
of encoders, will be described. In this case, as an example,
a calibration process of the position coordinate in the
15 direction besides the measurement direction (the X-axis
direction) orthogonal to the measurement direction of the
measurement beam emitted from Y head 64 configuring each head
unit 62A and 62C will be described.

First of all, on starting this calibration processing,
20 main controller 20 drives wafer stage WST and moves Y scales
39Y₁ and 39Y₂ so that Y scales 39Y₁ and 39Y₂ are located under
head units 62A and 62C, respectively. For example, as shown
in FIG. 14, Y head 64_{A3}, which is the third head from the left
of head unit 62A, and Y head 64_{C5}, which is the second head
25 from the right of head unit 62C, are made to face Y scales
39Y₁ and 39Y₂, respectively.

Next, based on the measurement values of measurement
beams B4₁ and B4₂ of Y interferometer 16, or the measurement
values of Z interferometers 43A and 43B, main controller 20

rotates wafer stage WST only by a predetermined angle (the angle being θ) within the XY plane with optical axis AX of projection optical system PL serving as a center as shown by an arrow RV in FIG. 14, and acquires the measurement values of Y heads 64_{A3} and 64_{C5} (encoders 70A and 70C), which can be obtained during the rotation. In FIG. 14, vectors MA and MB, which correspond to the measurement values measured during the rotation of wafer stage WST by Y heads 64_{A3} and 64_{C5}, are respectively shown.

10 In this case, because θ is a very small angle, $MA = b \cdot \theta$ and $MB = a \cdot \theta$ are valid, and a ratio MA/MB of the magnitude of vectors MA and MB is equal to a ratio a/b , which is a ratio of the distance from the rotation center to the irradiation point (also referred to as a detection point of the encoder or the head) of each measurement beam emitted from Y heads 15 64_{A3} and 64_{C5}, respectively.

 Therefore, main controller 20 computes distances b and a , or more specifically, the X-coordinate values of the irradiation points of the measurement beams emitted from Y heads 64_{A3} and 64_{C5}, based on the measurement values of encoders 20 70A and 70C and predetermined angle θ obtained from the measurement values of each of measurement beams B4₁ and B4₂ of interferometer 16, respectively, or, furthermore performs a calculation based on the X-coordinate values that have been 25 computed, and computes the positional shift amount (more specifically, correction information of the positional shift amount) of the irradiation points of the measurement beams emitted from Y heads 64_{A3} and 64_{C5}, respectively, in the X-axis direction with respect to the design position.

Further, in the case wafer stage WST is located at the position shown in FIG. 14, in actual practice, head units 62B and 62D face X scales $39X_1$ and $39X_2$, respectively. Accordingly, on the rotation of wafer stage WST described above, main controller 20 simultaneously acquires the measurement values of each X head 66 of head units 62B and 62D that respectively face X scales $39X_1$ and $39X_2$ (encoders 70B and 70D). Then, in a manner similar to the description above, main controller 20 computes the Y-coordinate values of the irradiation point of the measurement beams emitted from X head 66, respectively, which each face X scale $39X_1$ and $39X_2$, or, furthermore performs a calculation based on the computation results, and computes the positional shift amount (more specifically, correction information of the positional shift amount) of the irradiation point of the measurement beams emitted from the respective X heads in the Y-axis direction with respect to the design position.

Next, main controller 20 moves wafer stage WST in the X-axis direction at a predetermined pitch, and by performing a processing in the procedure similar to the procedure described above at each positioning position, main controller 20 can obtain the X-coordinate values of the irradiation point of the measurement beams emitted from the heads, or the positional shift amount (more specifically, correction information of the positional shift amount) in the X-axis direction with respect to the design position also for the remaining Y heads of head units 62A and 62C.

Further by moving in the Y-axis direction at a predetermined pitch from the position shown in FIG. 14 and

performing a processing in the procedure similar to the procedure described above at each positioning position, main controller 20 can obtain the Y-coordinate values of the irradiation point of the measurement beams emitted from the heads or the positional shift amount (more specifically, correction information of the positional shift amount) in the Y-axis direction with respect to the design position, also for the remaining X heads of head units 62B and 62D.

Further, in a method similar to Y head 64 described above, main controller 20 acquires the X-coordinate values of the irradiation point of the measurement beam emitted from the heads or the positional shift amount (more specifically, correction information of the positional shift amount) in the X-axis direction with respect to the design position, also for Y heads 64y₁ and y₂.

In the manner described above, main controller 20 can acquire the X-coordinate values of the irradiation point of the measurement beam emitted from the heads or the positional shift amount (more specifically, correction information of the positional shift amount) in the X-axis direction with respect to the design position for all Y heads 64, 64y₁, and 64y₂, and the Y-coordinate values of the irradiation point of the measurement beam emitted from the heads or the positional shift amount (more specifically, correction information of the positional shift amount) in the Y-axis direction with respect to the design position also for all X heads 66, therefore, the information that has been acquired is stored in a storage device, such as, for example, memory 34. The X-coordinate values or the Y-coordinate values of the

irradiation point of the measurement beam of each head or the positional shift amount in the X-axis direction or the Y-axis direction with respect to the design position of each head stored in memory 34, will be used such as when converting the measurement values of an encoder into positional information within the XY plane of wafer stage WST, as it will be described later on. Incidentally, in the case such as when converting the measurement values of an encoder into positional information within the XY plane of wafer stage WST or the like described later on, design values are used for the Y-coordinate values of the irradiation point of the measurement beam of each Y head, and the X-coordinate values of the irradiation point of the measurement beam of each X head. This is because since the influence that the position coordinates of each head in the measurement direction has on the control accuracy of the position of wafer stage WST is extremely weak, (the effectiveness to the control accuracy is extremely slow), it is sufficient enough to use the design values.

Now, in the case the optical axis of the heads of the encoder substantially coincides with the Z-axis, and the pitching amount, rolling amount, and yawing amount of wafer stage WST are all zero, as it is obvious from formulas (10) and (11) above, measurement errors of the encoder described above due to the attitude of wafer table WTB are not supposed to occur, however, even in such a case, the measurement errors of the encoder are not actually zero. This is because the surface of Y scales 39Y₁ and 39Y₂, and X scales 39X₁ and 39X₂ (the surface of the second water repellent plate 28b) is not an ideal plane, and is somewhat uneven. When the surface of

the scale (to be more precise, the diffraction grating surface, and including the surface of a cover glass in the case the diffraction grating is covered with the cover glass) is uneven, the scale surface will be displaced in the Z-axis direction
5 (move vertically), or be inclined with respect to the heads of the encoder even in the case when wafer stage WST moves along a surface parallel to the XY plane. This consequently means none other than a relative motion occurs in a direction besides the measurement direction between the head and the
10 scale, and as it has already been described, such a relative motion becomes a cause of the measurement error.

Further, as shown in FIG. 15, for example, in the case of measuring a plurality of measurement points P_1 and P_2 on the same scale 39X using a plurality of heads 66A and 66B,
15 when the tilt of the optical axis of the plurality of heads 66A and 66B is different and there is also an unevenness (including inclination) to the surface of scale 39X, as is obvious from $\Delta X_A \neq \Delta X_B$ shown in FIG. 15, the influence that the unevenness has on the measurement values will differ for
20 each head depending on the tilt difference. Accordingly, in order to remove such difference in the influence, it will be necessary to obtain the unevenness of the surface of scale 39X. The unevenness of the surface of scale 39X may be measured, for example, using a measurement device besides the encoder
25 such as the Z sensor previously described, however, in such a case, because the measurement accuracy of the unevenness is set according to the measurement resolution of the measurement device, in order to measure the unevenness with high precision, a possibility may occur of having to use a

sensor that has a higher precision and is more costly than the sensor necessary to fulfill the original purpose as a Z sensor.

Therefore, in the embodiment, a method of measuring the unevenness of the surface of a scale using the encoder system itself is employed. Following is a description of the method.

As shown in the graph (an error characteristics curve) of FIG. 12, which shows a change characteristic of the measurement values of the encoder (head) corresponding to the Z leveling of wafer stage WST previously described, only one point can be found in the Z-axis direction for each encoder head where the head has no sensibility to the tilt operation of wafer stage WST, or more specifically, a singular point where the measurement error of the encoder becomes zero regardless of the angle of inclination of wafer stage WST to the XY plane. If this point can be found by moving wafer stage WST similarly as when acquiring the stage position induced error correction information previously described, the point (a Z position) can be positioned the singular point with respect to the encoder head. If such an operation to find the singular point is performed on a plurality of measurement points on the scale, the shape (unevenness) of the surface of the scale can be obtained.

(a) Therefore main controller 20 first of all drives wafer stage WST via stage drive system 124, while monitoring the measurement values of Y interferometer 16, X interferometer 126, and Z interferometers 43A and 43B of interferometer system 118, and as shown in FIG. 16, makes an arbitrary Y head of head unit 62A, such as for example, Y head

64_{A2} in FIG. 16, face the vicinity of the end section of Y scale 39Y₁ on the +Y side. Then, main controller 20 changes the pitching amount (θ x rotation quantity) of wafer stage WST at the position in at least two stages as is previously
5 described, and in a state where the attitude of wafer stage WST at the time of change is maintained for every change, main controller 20 scans (moves) wafer stage WST in the Z-axis direction in a predetermined stroke range while irradiating a detection light on a point of Y scale 39Y₁ subject to
10 measurement from Y head 64_{A2}, and samples the measurement results of Y head 64_{A2} (encoder 70A) that faces Y scale 39Y₁ during the scan (movement). Incidentally, the sampling above is performed while maintaining the yawing amount (and rolling amount) of wafer stage WST at zero.

15 Then, by performing a predetermined computation based on the sampling results, main controller 20 obtains an error characteristics curve (refer to FIG. 12) at the point described above subject to the measurement of encoder 70A corresponding to the Z position of wafer stage WST for a plurality of
20 attitudes, and sets the intersecting point of the plurality of error characteristics curves, or more specifically, sets the point where the measurement error of encoder 70A above becomes zero regardless of the angle of inclination of wafer stage WST with respect to the XY plane as the singular point
25 at the measurement point, and obtains Z positional information z_1 (refer to FIG. 17A) of the singular point.

(b) Next, main controller 20 steps wafer stage WST in the +Y-direction by a predetermined amount via stage drive system 124 while maintaining the pitching amount and rolling

amount of wafer stage WST at zero, while monitoring the measurement values of Y interferometer 16, X interferometer 126, and Z interferometers 43A and 43B of interferometer system 118. This step movement is performed at a speed slow enough
 5 so that measurement errors caused by air fluctuation of the interferometers can be ignored.

(c) Then, at a position after the step movement, as in (a) above, main controller 20 obtains a Z positional information z_p (in this case, $p=2$) of the singular point of
 10 encoder 70A above at the position.

After this operation, by repeating the operations similar to the ones described in (b) and (c) above, main controller 20 obtains a Z positional information z_p ($p=2, 3, \dots, i, \dots, k, \dots, n$) in a plurality of (e. g.
 15 $n-1$) measurement points set at a predetermined interval in the Y-axis direction on scale 39Y₁.

FIG. 17B shows a z positional information z_i of the singular point at the i^{th} measurement point that was obtained in the manner described above, and FIG. 17C shows a z positional
 20 information z_k of the singular point at the k^{th} measurement point.

(d) Then, based on Z positional information $z_1, z_2, \dots, z_n$ of the singular point obtained for each of the plurality of measurement points above, main controller 20
 25 obtains the unevenness of the surface of scale 39Y₁. As shown in FIG. 17D, if one end of a double-sided arrow showing Z position z_p of the singular point in each measurement point on scale 39Y₁ is made to coincide with a predetermined reference line, the curve which links the other end of each double-sided

arrow indicates the shape of the surface (unevenness) of scale 39Y₁. Accordingly, main controller 20 obtains function $z = f_1(y)$ that expresses this unevenness by performing curve fitting (a least square approximation) on the point at the
5 other end of each double-sided arrow, and stores the function in memory 34. Incidentally, y is a Y-coordinate of wafer stage WST measured with Y interferometer 16.

(e) In a similar manner described above, main controller 20 obtains function $z = f_2(y)$ that expresses the
10 unevenness of Y scale 39Y₂, function $z = g_1(x)$ that expresses the unevenness of X scale 39X₁, and, function $z = g_2(x)$ that expresses the unevenness of X scale 39X₂, respectively, and stores them in memory 34. Incidentally, x is an X-coordinate of wafer stage WST measured with X interferometer 126.

15 In this case, in the case of obtaining the error characteristics curve (refer to FIG. 12) described above at each measurement point on each scale, when an error characteristics curve whose measurement error always becomes zero regardless of the change of Z is obtained, the pitching
20 amount (or rolling amount) of wafer stage WST at the point when the error characteristics curve was obtained corresponds to an inclined quantity of the scale surface at the measurement point. Accordingly, in the method above, information on inclination at each measurement point can also be obtained,
25 in addition to the height information of the scale surface. This arrangement allows fitting with higher precision when the curve fitting described above is performed.

Now, the scale of the encoder lacks in mechanical long-term stability, such as in the diffraction grating

deforming due to thermal expansion or other factors by the passage of use time, or the pitch of the diffraction grating changing partially or entirely. Therefore, because the errors included in the measurement values grow larger with the passage of use time, it becomes necessary to correct the errors. Hereinafter, an acquisition operation of correction information of the grating pitch of the scale and of correction information of the grating deformation performed in exposure apparatus 100 of the embodiment will be described, based on FIG. 18

In FIG. 18, measurement beams $B4_1$ and $B4_2$ are arranged symmetric to straight line LV previously described, and the substantial measurement axis of Y interferometer 16 coincides with straight line LV, which passes through the optical axis of projection optical system PL and is parallel to the Y-axis direction. Therefore, according to Y interferometer 16, the Y position of wafer table WTB can be measured without Abbe error. Similarly, measurement beams $B5_1$ and $B5_2$ are arranged symmetric to straight line LH previously described, and the substantial measurement axis of X interferometer 126 coincides with straight line LH, which passes through the optical axis of projection optical system PL and is parallel to the X-axis direction. Therefore, according to X interferometer 126, the X position of wafer table WTB can be measured without Abbe error.

First of all, an acquisition operation of correction information of the deformation of the grid line (warp of the grid line) of the X scale, and correction information of the grating pitch of the Y scale will be described. In this case,

to simplify the description, reflection surface 17b is to be an ideal plane. Further, prior to this acquisition operation, a measurement of the unevenness information of the surface of each scale described above is performed, and function $z = f_1(y)$ that expresses the unevenness of Y scale 39Y₁, function $z = f_2(y)$ that expresses the unevenness of Y scale 39Y₂, function $z = g_1(x)$ that expresses the unevenness of X scale 39X₁, and function $z = g_2(x)$ that expresses the unevenness of X scale 39X₂, are to be stored in memory 34.

10 First of all, main controller 20 reads function $z = f_1(y)$, function $z = f_2(y)$, function $z = g_1(x)$ and function $z = g_2(x)$ stored in memory 34 into the internal memory.

Next, at a speed low enough so that the short-term variation of the measurement values of Y interferometer 16 can be ignored and also in a state where the measurement value of X interferometer 126 is fixed to a predetermined value, main controller 20 moves wafer stage WST based on the measurement values of Y interferometer 16, and Z interferometers 43A and 43B, for example, in at least one direction of the +Y-direction and the - Y direction within the effective stroke range mentioned earlier as is indicated by arrows F and F' in FIG. 18, in a state where the pitching amount, the rolling amount, and the yawing amount are all maintained at zero. During this movement, while correcting the measurement values (the output) of Y linear encoders 70A and 70C using the function $z = f_1(y)$ and function $z = f_2(y)$ described above, respectively, main controller 20 takes in the measurement values after the correction and the measurement values (or to be more precise, measurement values

of measurement beams $B4_1$ and $B4_2$) of Y interferometer 16 at a predetermined sampling interval, and based on each measurement value that has been taken in, obtains a relation between the measurement values of Y linear encoders 70A and 70C (output of encoder 70A - the measurement values corresponding to function $f_1(y)$, output of encoder 70C - the measurement values corresponding to function $f_2(y)$) and the measurement values of Y interferometer 16. More specifically, in the manner described above, main controller 20 obtains a grating pitch (the distance between adjacent grid lines) of Y scales $39Y_1$ and $39Y_2$ which are sequentially placed opposing head units 62A and 62C with the movement of wafer stage WST and correction information of the grating pitch. As the correction information of the grating pitch, for example, in the case a horizontal axis shows the measurement values of the interferometer and a vertical axis shows the measurement values (the measurement values whose errors due to the unevenness of the scale surface has been corrected) of the encoder, a correction map which shows the relation between the two using a curve can be obtained. Because the measurement values of Y interferometer 16 in this case are obtained when wafer stage WST was scanned at an extremely low speed as was previously described, the measurement values hardly include any short-term variation errors due to air fluctuation, as well as long-term variation errors, and it can be said that the measurement values are accurate values in which the errors can be ignored.

Further, during the movement of wafer stage WST described above, by statistically processing the measurement

values (the measurement values of X linear encoders 70B and 70D) obtained from a plurality of X heads 66 of head units 62B and 62D placed sequentially opposing X scales 39X₁ and 39X₂ with the movement, such as, for example, averaging (or
5 performing weighted averaging), main controller 20 also obtains correction information of the deformation (warp) of grid lines 37 which sequentially face the plurality of X heads 66. This is because in the case reflection surface 17b is an ideal plane, the same blurring pattern should appear
10 repeatedly in the process when wafer stage WST is sent in the +Y-direction or the - Y direction, therefore, if averaging or the like is performed on the measurement data acquired with the plurality of X heads 66, it becomes possible to precisely obtain correction information of the deformation (warp) of
15 grid lines 37 which sequentially face the plurality of X head 66.

Incidentally, in a normal case where reflection surface 17b is not an ideal plane, by measuring the unevenness (warp) of the reflection surface and obtaining the correction data
20 of the warp in advance and performing movement of wafer stage WST in the +Y-direction or the - Y-direction while controlling the X position of wafer stage WST, based on the correction data instead of fixing the measurement value of X
interferometer 126 to the predetermined value on the movement
25 of wafer stage WST in the +Y-direction or the - Y direction described above, wafer stage WST can be made to move precisely in the Y-axis direction. In this manner, the same correction information of the grating pitch of the Y scale and the same correction information of the deformation (warp) of grid lines

37 can be obtained as in the description above. Incidentally, the measurement data acquired with the plurality of X heads 66 described above is a plurality of data at different location references of reflection surface 17b, and because X heads 66 measure deformation (warp) of the same grid line 37, there is a collateral effect of the warp correction residual of the reflection surface being averaged and approaching its true value (in other words, by averaging the measurement data (warp information of grid line 37) acquired by the plurality of X heads, the effect of the warp residual can be weakened) by the averaging or the like described above.

Next, acquisition operations of correction information of deformation of the grid lines (warp of the grid lines) of the Y scale and correction information of the grating pitch of the X scale will be described. In this case, to simplify the description, reflection surface 17a is to be an ideal plane. In this case, a processing as in the case of the correction described above, but with the X-axis direction and the Y-axis direction interchanged, should be performed.

More specifically, at a speed low enough so that the short-term variation of the measurement values of X interferometer 126 can be ignored and also in a state where the measurement value of Y interferometer 16 is fixed to a predetermined value, main controller 20 moves wafer stage WST based on the measurement values of X interferometer 126, Y interferometer 16, and Z interferometers 43A and 43B, for example, in at least one direction of the +X-direction and the - X-direction within the effective stroke range mentioned earlier, in a state where the pitching amount, the rolling

amount, and the yawing amount are all maintained at zero. During this movement, while correcting the measurement values of X linear encoders 70B and of 70D using the function $z = g_1(x)$ and function $z = g_2(x)$ described above, respectively, 5 main controller 20 takes in the measurement values after the correction and the measurement values of X interferometer 126 at a predetermined sampling interval, and based on each measurement value that has been taken in, obtains a relation between the measurement values of X linear encoders 70B and 10 70D (output of encoder 70B - the measurement values corresponding to function $g_1(x)$, output of encoder 70D - the measurement values corresponding to function $g_2(x)$) and the measurement values of X interferometer 126. More specifically, in the manner described above, main controller 15 20 obtains a grating pitch (the distance between adjacent grid lines) of X scales 39X₁ and 39X₂ which are sequentially placed opposing head units 62B and 62D with the movement of wafer stage WST and the correction information of the grating pitch. As the correction information of the grating pitch, for example, 20 in the case a horizontal axis shows the measurement values of the interferometer and a vertical axis shows the measurement values (the measurement values whose errors due to the unevenness of the scale surface has been corrected) of the encoder, a map which shows the relation between the two using 25 a curve can be obtained. Because the measurement values of X interferometer 126 in this case are obtained when wafer stage WST was scanned at an extremely low speed as was previously described, the measurement values hardly include any short-term variation errors due to air fluctuation, as well

as long-term variation errors, and it can be said that the measurement values are accurate values in which the errors can be ignored.

Further, during the movement of wafer stage WST
5 described above, by statistically processing the measurement values (the measurement values of Y linear encoders 70A and 70C) obtained from a plurality of Y heads 64 of head units 62A and 62C placed sequentially opposing Y scales 39Y₁ and 39Y₂ previously described with the movement, such as, for example,
10 averaging (or performing weighted averaging), main controller 20 also obtains correction information of the deformation (warp) of grid lines 38 which sequentially face the plurality of Y heads 64. This is because in the case reflection surface 17a is an ideal plane, the same blurring pattern should appear
15 repeatedly in the process when wafer stage WST is sent in the +X-direction or the - X direction, therefore, if averaging or the like is performed on the measurement data acquired with the plurality of Y heads 64, it becomes possible to precisely obtain correction information of the deformation (warp) of
20 grid lines 38 which sequentially face the plurality of Y head 64.

Incidentally, in a normal case where reflection surface 17a is not an ideal plane, by measuring the unevenness (warp) of the reflection surface and obtaining the correction data
25 of the warp in advance and performing movement of wafer stage WST in the +X-direction or the -X-direction while controlling the Y position of wafer stage WST, based on the correction data instead of fixing the measurement value of Y interferometer 16 to the predetermined value on the movement

of wafer stage WST in the +X-direction or the -X-direction described above, wafer stage WST can be made to move precisely in the X-axis direction. In this manner, the same correction information of the grating pitch of the X scale and the
5 correction information of the deformation (warp) of grid lines 38 can be obtained as in the description above.

As is described above, main controller 20 obtains correction information on grating pitch of the Y scales and correction information on deformation (warp) of grid lines
10 37, and correction information on grating pitch of the X scales and correction information on deformation (warp) of grid lines 38 at each predetermined timing, for example, with respect to each lot, or the like.

And, during processing of the lot or the like, main
15 controller 20 performs movement control of wafer stage WST in the Y-axis direction, using Y scales 39Y₁ and 39Y₂ and head units 62A and 62C, or more specifically, using Y linear encoders 70A and 70C, while correcting the measurement values obtained from head units 62A and 62C (more specifically, the
20 measurement values of encoders 70A and 70C), based on correction information of the grating pitch and correction information of the deformation (warp) of grid line 38 referred to above and stage position induced error correction information corresponding to Z position z, pitching amount
25 θ_x , and yawing amount θ_z of wafer stage WST measured by interferometer system 118. By this operation, it becomes possible for main controller 20 to perform movement control of wafer stage WST in the Y-axis direction with good precision using Y linear encoders 70A and 70C, without being affected

by temporal change of the grating pitch of the Y scale and the warp of each grating (line) that makes up the Y scale, and also without being affected by the change of position of wafer stage WST in a direction besides the measurement
5 direction (relative motion between the head and the scale in a direction besides the measurement direction).

And, during processing of the lot or the like, main controller 20 performs movement control of wafer stage WST in the X-axis direction, using X scales 39X₁ and 39X₂ and head
10 units 62B and 62D, or more specifically, using X linear encoders 70B and 70D, while correcting the measurement values obtained from head units 62B and 62D (more specifically, the measurement values of encoders 70B and 70D), based on
correction information of the grating pitch and correction
15 information of the deformation (warp) of grid line 37 referred to above and stage position induced error correction information corresponding to Z position z, rolling amount θ_y , and yawing amount θ_z of wafer stage WST measured by
interferometer system 118. By this operation, it becomes
20 possible for main controller 20 to perform movement control of wafer stage WST in the X-axis direction with good precision using X linear encoders 70B and 70D, without being affected
by temporal change of the grating pitch of the X scale and the warp of each grating (line) that make up the X scale, and
25 also without being affected by the change of position of wafer stage WST in a direction besides the measurement direction (relative motion between the head and the scale in a direction besides the measurement direction).

Incidentally, in the description above, the correction

information of the grating pitch and the grid line warp was acquired for both the Y scale and the X scale, however, the present invention is not limited to this, and the correction information of the grating pitch and the grid line warp can be acquired only for either the Y scale or the X scale, or the correction information of only either the grating pitch or the grid line warp can be acquired for both the Y scale and the X scale. For example, in the case where only the acquisition of the correction information of the warp of grid line 37 of the X scale is performed, wafer stage WST can be moved in the Y-axis direction based on the measurement values of Y linear encoders 70A and 70C, without necessarily using Y interferometer 16. Similarly, in the case where only the acquisition of the correction information of the warp of grid line 38 of the Y scale is performed, wafer stage WST can be moved in the X-axis direction based on the measurement values of X linear encoders 70B and 70D, without necessarily using X interferometer 126. Further, either one of the stage position induced error previously described or the measurement error (hereinafter also referred to as a scale induced error) of the encoder which occurs due to the scale (for example, degree of flatness of the grating surface (surface smoothness) and/or grating formation error (including pitch error, grid line warp and the like) and the like) can be compensated.

Next, a switching process of the encoder used for position control of wafer stage WST in the XY plane that is executed during the actual processing of a lot or the like, or more specifically, a linkage process between a plurality

of encoders will be described, after processing such as the acquisition of the stage position induced error correction information, acquisition of positional information of each head previously described, unevenness measurement of the surface of the scale, and the acquisition of correction information of the grating pitch of the scale and the correction information of the grating deformation and the like are performed in advance.

In this case, first of all, prior to describing the linkage process of the plurality of encoders, a concrete method of converting the corrected measurement values of the encoder into the position of wafer stage WST, which is the premise, will be described, using FIGS. 19A and 19B. In this case, in order to simplify the description, the degrees of freedom of wafer stage WST is to be three degrees of freedom (X , Y , and θ z).

FIG. 19A shows a reference state where wafer stage WST is at the origin of coordinates $(X, Y, \theta z) = (0, 0, 0)$. From this reference state, wafer stage WST is driven in a range where encoders (Y heads) Enc1 and Enc2 and encoder (X head) Enc3 do not move away from the scanning areas of their opposing scales $39Y_1$, $39Y_2$ and $39X_1$. The state where wafer stage WST is moved to position $(X, Y, \theta z)$ in the manner described above is shown in FIG. 19B.

Here, let position coordinates (X, Y) of the measurement points of encoders Enc1, Enc2, and Enc3 on the XY coordinate system be (p_1, q_1) , (p_2, q_2) , and (p_3, q_3) , respectively. The positional information of the irradiation point of the measurement beam, which was acquired in the case of the

calibration of the head position described earlier is read from memory 34 and used for X-coordinate values p_1 and q_2 of encoders Enc1 and Enc2 and Y-coordinate value q_3 of encoder Enc3, and the design positional information of the irradiation point of the measurement beam is read from memory 34 and used for Y-coordinate values q_1 and p_2 of encoders Enc1 and Enc2 and X-coordinate value p_3 of encoder Enc3.

The X head and the Y head respectively measure the relative distance from central axes LL and LW of wafer stage WST. Accordingly, measurement values C_x and C_y of the X head and the Y head can be expressed, respectively, as in the following formulas (12a) and (12b).

$$C_x = r' \cdot ex' \dots (12a)$$

$$C_y = r' \cdot ey' \dots (12b)$$

In this case, ex' and ey' are X' and Y' unit vectors in a relative coordinate system $(X', Y', \theta z')$ set on wafer stage WST, and have a relation as in the following formula (13) with X and Y unit vectors ex and ey in the reference coordinate system $(X, Y, \theta z)$.

$$\begin{pmatrix} ex' \\ ey' \end{pmatrix} = \begin{pmatrix} \cos \theta z & \sin \theta z \\ -\sin \theta z & \cos \theta z \end{pmatrix} \begin{pmatrix} ex \\ ey \end{pmatrix} \dots (13)$$

Further, r' is a position vector of the encoder in the relative coordinate system, and r' is given $r' = r - (O' - O)$, using position vector $r = (p, q)$ in the reference coordinate system. Accordingly, formulas (12a) and (12b) can be

rewritten as in the following formulas (14a) and (14b).

$$C_x = (p-X) \cos\theta z + (q-Y) \sin\theta z \dots\dots (14a)$$

$$C_y = - (p-X) \sin\theta z + (q-Y) \cos\theta z \dots\dots (14b)$$

5

Accordingly, when wafer stage WST is located at the coordinate (X, Y, θz) as shown in FIG. 19B, the measurement values of three encoders can be expressed theoretically as in the next formulas (15a) to (15c) (also referred to as a
10 relationship of the affine transformation).

$$C_1 = - (p_1-X) \sin\theta z + (q_1-Y) \cos\theta z \dots\dots (15a)$$

$$C_2 = - (p_2-X) \sin\theta z + (q_2-Y) \cos\theta z \dots\dots (15b)$$

$$C_3 = (p_3-X) \cos\theta z + (q_3-Y) \sin\theta z \dots\dots (15c)$$

15

Incidentally, in the reference state shown in FIG. 19A, according to simultaneous equations (15a) to (15c), then $C_1 = q_1$, $C_2 = q_2$, and $C_3 = p_3$. Accordingly, in the reference state, if the measurement values of the three encoders Enc1, Enc2,
20 and Enc3 are initialized to q_1 , q_2 , and p_3 respectively, then the three encoders will show theoretical values given by formulas (15a) to (15c) with respect to displacement (X, Y, θz) of wafer stage WST from then onward.

In simultaneous equations (15a) to (15c), three formulas
25 are given to the three variables (X, Y, θz). Accordingly, if dependent variables C_1 , C_2 , and C_3 are given in the simultaneous equations (15a) to (15c), variables X, Y, and θz can be obtained. In this case, when approximation $\sin\theta z \approx \theta z$ is applied, or even if an approximation of a higher order is applied, the

equations can be solved easily. Accordingly, the position of wafer stage WST (X , Y , θ_z) can be computed from measurement values C_1 , C_2 , and C_3 of the encoder.

Next, a linkage process performed during the switching
5 of the encoder head used for position control of wafer stage WST in the XY plane in the embodiment, or more specifically, an initial setting of a measurement value will be described, focusing on an operation of main controller 20.

In the embodiment, as is previously described, three
10 encoders (the X heads and the Y heads) constantly observe wafer stage WST within the effective stroke range of wafer stage WST, and when the switching process of the encoder is performed, four encoders will be made to observe wafer stage WST, as shown in FIG. 20.

15 At the moment when the switching process (linkage) of the encoder used for the position control of wafer stage WST within the XY plane is to be performed, encoders Enc1, Enc2, Enc3 and Enc4 are positioned above scales 39Y₁, 39Y₂, 39X₁, and 39X₂, respectively, as shown in FIG. 20. When having a
20 look at FIG. 20, it looks as though the encoder is going to be switched from encoder Enc1 to encoder Enc4, however, as is obvious from the fact that the measurement direction is different in encoder Enc1 and encoder Enc4, it does not have any meaning even if the measurement values (count values) of
25 encoder Enc1 are given without any changes as the initial value of the measurement values of encoder Enc4 at the timing when linkage process is performed.

Therefore, in the embodiment, main controller 20 switches from measurement / servo by the three encoders Enc1,

Enc2 and Enc3 to measurement / servo by the three encoders Enc2, Enc3 and Enc4. More specifically, as it can be seen from FIG. 20, this method is different from the concept of a normal encoder linkage, and in this method the linkage is made not
 5 from one head to another head, but from a combination of three heads (encoders) to a combination of another three heads (encoders). Incidentally, in the three heads and another three heads, the different head is not limited to one. Further, in FIG. 20, encoder Enc1 was switched to encoder Enc4, however,
 10 instead of encoder Enc4, for example, the encoder can be switched, for example, to the encoder adjacent to encoder Enc3.

First of all, main controller 20 solves the simultaneous equations (15a) to (15c) above based on the measurement values C_1 , C_2 , and C_3 of encoders Enc1, Enc2, and Enc3, and computes
 15 positional information (X , Y , θ_z) of wafer stage WST within the XY plane.

Next, main controller 20 substitutes X and θ_z computed above into the affine transformation of the next formula (16), and determines the initial value of the measurement values
 20 of encoder (X head) Enc4.

$$C_4 = (p_4 - X) \cos \theta_z + (q_4 - Y) \sin \theta_z \dots\dots (16)$$

In formula (16) above, p_4 and q_4 are the X-coordinate value and the Y-coordinate value at the measurement point of
 25 encoder Enc4 (detection point). As Y-coordinate value q_4 of encoder Enc4, the positional information of the irradiation point of the measurement beam which was acquired on calibration of the head position previously described is read from memory

34 and is used, while as X-coordinate value p_4 of encoder Enc4, the design positional information of the irradiation point of the measurement beam is read from memory 34 and is used.

By giving initial value C_4 as an initial value of encoder
 5 Enc4, linkage will be completed without any contradiction, having maintained the position $(X, Y, \theta z)$ of wafer stage WST in directions of three degree of freedom. From then onward, the following simultaneous equations (15b) to (15d) are solved, using the measurement values C_2 , C_3 , and C_4 of encoders Enc2,
 10 Enc3, and Enc4 which are used after the switching, and a position coordinate $(X, Y, \theta z)$ of wafer stage WST is computed.

$$C_2 = - (p_2 - X) \sin \theta z + (q_2 - Y) \cos \theta z \dots (15b)$$

$$C_3 = (p_3 - X) \cos \theta z + (q_3 - Y) \sin \theta z \dots (15c)$$

$$15 \quad C_4 = (p_4 - X) \cos \theta z + (q_4 - Y) \sin \theta z \dots (15d)$$

Incidentally, in the case the fourth encoder is a Y head, then instead of using theoretical formula (15d), the following theoretical formula (15e) can be used in simultaneous
 20 equations (15b) (15c) (15e).

$$C_4 = - (p_4 - X) \sin \theta z + (q_4 - Y) \cos \theta z \dots (15e)$$

However, because measurement value C_4 computed above is
 25 a measurement value of a corrected encoder whose various measurement errors of the encoders previously described have been corrected, main controller 20 performs inverse correction on measurement value C_4 and computes a raw value C_4' which is the value before correction, and determines raw

value C_4' as the initial value of the measurement value of encoder Enc4, using the stage position induced error correction information, the scale induced error correction information (e.g., the degree of flatness of the grating surface (flatness), and/or the correction information of the grating pitch of the scale (and the correction information of the grating deformation) and the like) and the like previously described.

In this case, the inverse correction refers to the processing of computing measurement value C_4' based on measurement value C_4 , under the hypothesis that C_4 is a measurement value of the encoder after correction when measurement value C_4' of the encoder on which no correction has been performed is corrected using the stage position induced error correction information previously described, the scale induced error correction information described above and the like.

Now, the position control interval (control sampling interval) of wafer stage WST, as an example, is 96 [μ sec], however, the measurement interval (measurement sampling interval) of an interferometer or an encoder has to be at a much higher speed. The reason why the sampling of the interferometer and the encoder has to be performed at a higher-speed than the control sampling is because both the interferometer and the encoder count the intensity change (fringe) of the interference light, and when the sampling becomes rough, measurement becomes difficult.

However, with the position servo control system of wafer stage WST, the system updates the current position of wafer

stage WST at every control sampling interval of 96 [μ sec], performs calculation to set the position to a target position, and outputs thrust command values and the like. Accordingly, the positional information of the wafer stage is necessary
5 at every control sampling interval of 96 [μ sec], and the positional information in between the sampling intervals will not be necessary in the position control of wafer stage WST. The interferometer and the encoder merely perform sampling at a high speed so as not to lose track of the fringe.

10 Therefore, in the embodiment, at all times while wafer stage WST is located in the effective stroke range previously described, main controller 20 continues to receive the measurement values (count values) from each encoder (a head) of the encoder system, regardless of whether or not the encoder
15 watches the scale. And, main controller 20 performs the switching operation of the encoders (linkage operation between the plurality of encoders) previously described, in synchronization with the timing of the position control of the wafer stage performed every 96 [μ sec]. In such an
20 arrangement, the electrically high-speed switching operation of an encoder will not be required, which means that costly hardware to realize such a high-speed switching operation does not necessarily have to be arranged. FIG. 21 conceptually shows the timing of position control of wafer stage WST, the
25 uptake of the count values of the encoder, and the switching of the encoder, which are performed in the embodiment. In FIG. 21, a reference code CSCK shows a generation timing of a sampling clock of the position control of wafer stage WST, and a reference code MSCK shows a generation timing of a

measurement sampling clock of the encoder (and the interferometer). Further, a reference code CH typically shows the switching (linkage) of the encoder.

Now, in the description above, the switching that could
5 be performed from one combination of heads (encoders) to another combination of heads (encoders), and the timing when the switching can be performed are to be known, however, they also must be known in the actual sequence as well. It is also preferable to prepare the scheduling of the timing to carry
10 out the linkage in advance.

Therefore, in the embodiment, main controller 20 prepares the schedule for the switching (the switching from one combination of three heads (e. g., Enc1, Enc2, and Enc3) to another combination of three heads (e. g., Enc4, Enc2, and
15 Enc3), and the timing of the switch) of the three encoders (heads) which are used for measuring the positional information of wafer stage WST in directions of three degrees of freedom (X, Y, θ_z) within the XY plane, based on the movement course (target track) of wafer stage WST, and stores the
20 scheduling result in the storage device such as memory 34.

In this case, if a retry (redoing) is not considered, the contents of the schedule in every shot map (an exposure map) becomes constant, however, in actual practice, because a retry must be considered, it is preferable for main
25 controller 20 to constantly update the schedule slightly ahead while performing the exposure operation.

Incidentally, in the embodiment above, because the description was made related to the principle of the switching method of the encoder used for position control of wafer stage

WST, expressions such as encoder (head) Enc1, Enc2, Enc3, and Enc4 were used, however, it goes without saying that head Enc1 and Enc2 indicate either Y head 64 of head units 62A and 62C or a pair of Y heads 64y₁ and 64y₂, representatively, and heads
 5 Enc3 and Enc4 indicates X head 66 of head unit 62B and 62D, representatively. Further, for similar reasons, in FIGS. 19A, 19B and 20, the placement of encoders (heads) Enc1, Enc2, Enc3 and the like is shown differently from the actual placement (FIG. 3 and the like).

10 « Generalization of Switching and Linkage Principle»

In the embodiment, in order to measure the position coordinates of wafer stage WST in directions of three degrees of freedom (X, Y, θ_z), among the X encoders (heads) and Y encoders (heads) that constitute encoder systems 70A to 70D,
 15 at least three heads which at least include one X head and at least two Y heads are constantly used. Therefore, when the head which is to be used is switched along with the movement of wafer stage WST, a method of switching from a combination of three heads to another combination of three heads is
 20 employed, so as to continuously link the measurement results of the stage position before and after the switching. This method will be referred to as a first method.

However, when considering the basic principle of the switching and linkage process from a different point of view,
 25 it can also be viewed as a method of switching one head of the three heads that are used to another head. This method will be referred to as a second method. Now, the second method will be described, referring to a switching and linkage process from Y head 64_{c3} to 64_{c4} as an example, indicated by an arrow

e_1 in FIG. 7A.

The basic procedure of the switching process is, while both a first head 64_{c3} which will be suspended later and a second head 64_{c4} which will be newly used face the corresponding scale 39Y₂, main controller 20 executes the restoration of the second head 64_{c4} and the setting of the measurement values (linkage process), and the switching (and suspension of the first head 64_{c3}) of the head monitoring the measurement value.

On setting the measurement value (linkage process), main controller 20 predicts a measurement value C_{Y4} of the second head 64_{c4} using a measurement value C_{Y3} of the first head 64_{c3} . In this case, according to theoretical formula (14b), measurement values C_{Y3} and C_{Y4} of Y heads 64_{c3} and 64_{c4} follow formulas (17a) and (17b) below.

15

$$C_{Y3} = - (p_3 - X) \sin \theta z + (q_3 - Y) \cos \theta z \dots\dots (17a)$$

$$C_{Y4} = - (p_4 - X) \sin \theta z + (q_4 - Y) \cos \theta z \dots\dots (17b)$$

In this case, (p_3, q_3) and (p_4, q_4) are the X and Y setting positions (or to be more precise, the X and Y positions of the measurement points (detection points)) of Y heads 64_{c3} and 64_{c4} . To make it more simple, suppose that the Y setting positions of Y heads 64_{c3} and 64_{c4} are equal ($q_3 = q_4$). Under this supposition, according to formulas (17a) and (17b) above, the following formula (18) can be obtained.

25

$$C_{Y4} = C_{Y3} + (p_3 - p_4) \sin \theta z \dots\dots (18)$$

Accordingly, by substituting the measurement value of

first head 64_{C3} which will be suspended later into C_{Y3} on the right-hand side of formula (18) above and obtaining C_{Y4} on the left-hand side, the measurement value of the second head 64_{C4} which will be newly used can be predicted.

5 Predicted value C_{Y4} that has been obtained is to be set as the initial value of the measurement value of the second head 64_{C4} at a proper timing. After the setting, the first head 64_{C3} is suspended when it moves off scale $39Y_2$, which completes the switching and linkage process.

10 Incidentally, when the measurement value of the second head 64_{C4} is predicted using formula (18) above, a value of rotation angle θ_z , which is obtained from the measurement results of another head that is active, should be substituted into variable θ_z . In this case, another head that is active
15 is not limited to the first head 64_{C3} which is subject to switching, but includes all the heads that provide the measurement results necessary to obtain rotation angle θ_z . In this case, because the first head 64_{C3} is a head of head unit $62C$, rotation angle θ_z can be obtained using the first
20 head 64_{C3} , and for example, one of the heads of head unit $62A$ that faces Y scale $39Y_1$ during the switching. Or, a value of rotation angle θ_z , which can be obtained from the measurement results of X interferometer 126, Y interferometer 16, or Z interferometer 43A and 43B or the like of interferometer system
25 118 and the like can be substituted into variable θ_z .

Incidentally, the switching and linkage process between Y heads was explained as an example here, however, the switching and linkage process between X heads, and further, also the switching and linkage process between two heads

belonging to different head units such as between the X head and the Y head can also be explained similarly as the second method.

Therefore when the principle of the linkage process is
5 generalized, the measurement value of another head newly used is predicted so that the results of the position measurement of wafer stage WST is linked continuously before and after the switching, and the predicted value is set as the initial value of the measurement values of the second head. In this
10 case, in order to predict the measurement values of another head, theoretical formulas (14a) and (14b) and the measurement values of the active heads including the head which will be suspended later subject to the switching will be used as required. However, for the rotation angle in the θz direction
15 of wafer stage WST which is necessary on the linkage, a value which is obtained from the measurement results of interferometer system 118 can be used.

As is described above, even if it is premised that at least three heads are constantly used to measure the position
20 of wafer stage WST in directions of three degrees of freedom (X, Y, θz) as in the preceding first method, if focusing on only the two heads which are direct objects of the switching and linkage process without referring to the concrete procedure of predicting the measurement value of another head
25 newly used, the observation on the second method where one head out of the three heads used is switched to another head can be realized.

Incidentally, the description so far was made on the premise that the position of wafer stage WST in directions

of three degrees of freedom (X, Y, θ_z) was measured using at least three heads. However, even in the case of measuring the position of two or more in directions of m degrees of freedom (the choice of the degrees of freedom is arbitrary) using at least m heads, it is obvious that the observation of the second method where one head out of m heads used is switched to another head can be realized, as in the description above.

Next, a description will be made in which under a specific condition, an observation of a method (to be referred to as a third method) where a combination of two heads is switched to a combination of another two heads can be consistently realized.

In the example above, switching and linkage process between both heads 64_{C3} and 64_{C4} is executed, while Y heads 64_{C3} and 64_{C4} each face the corresponding Y scale $39Y_2$. During this operation, according to the placement of the scale and the head employed in exposure apparatus 100 of the embodiment, one Y head (expressed as 64_A) of the Y heads of head unit 62A faces Y scale $39Y_1$ and measures relative displacement of Y scale $39Y_1$ in the Y-axis direction. Therefore, a switching and linkage process will be considered from a first combination of Y heads 64_{C3} and 64_A to a second combination of Y heads 64_{C4} and 64_A .

According to theoretical formula (14b), a measurement value C_{YA} of Y head 64_A follows formula (17c) below.

$$C_{YA} = - (p_A - X) \sin \theta_z + (q_A - Y) \cos \theta_z \dots\dots (17c)$$

In this case, (p_A, q_A) is the X and Y setting position

(or to be more precise, the X and Y positions of the measurement point) of Y head 64_A. To make it more simple, suppose that Y setting position q_A of Y head 64_A is equal to Y setting positions q₃ and q₄ of Y heads 64_{C3} and 64_{C4} (q_A = q₃ = q₄).

5 When theoretical formulas (17a) and (17c), which measurement values C_{Y3} and C_{YA} of Y heads 64_{C3} and 64_A of the first combination follow, are substituted into theoretical formula (17b), which measurement value C_{Y3} of Y head 64_{C4} that is newly used follows, formula (19) below is derived.

10

$$C_{Y4} = (1-c)C_{Y3} - c \cdot C_{YA} \dots\dots (19)$$

However, constant $c = (p_3 - p_4) / (q_A - q_3)$. Accordingly, by substituting the measurement values of Y heads 64_{C3} and 64_A into C_{Y3} and C_{YA} on the right-hand side of formula (19) above and obtaining C_{Y4} on the left-hand side, the measurement value of Y head 64_{C4} newly used can be predicted.

15

Predicted value C_{Y4} that has been obtained is to be set as the measurement value of Y head 64_{C4} at a proper timing. After the setting, Y head 64_{C3} is suspended when it moves off scale 39Y₂, which completes the switching and linkage process.

20

Incidentally, according to the placement of the scale and the head employed in exposure apparatus 100 of the embodiment, at least one X head 66 faces X scale 39X₁ or 39X₂ and measures the relative displacement in the X-axis direction. Then, according to the measurement results of the three heads, which are one X head 66 and two Y heads 64_{C3} and 64_A, the position of wafer stage WST in directions of three degrees of freedom (X, Y, θ_z) is computed. However, in the example of the

25

switching and linkage process described above, X head 66 merely plays the role of a spectator, and the observation of the third method where a combination of two heads, Y heads 64_{C3} and 64_A is switched to a combination of another two heads, Y head 64_{C4} and 64_A, is consistently realized.

Accordingly, under the premise that the use of three heads is indispensable to measure the position of wafer stage WST in directions of three degrees of freedom (X, Y, θ_z), the first method was proposed as a general method of the switching and linkage process that could be applied to every case, regardless of the placement of the scale and the head employed in exposure apparatus 100 of the embodiment. And, based on the concrete placement of the scale and the head employed in exposure apparatus 100 of the embodiment and the concrete procedure of the linkage process, the observation of the third method could be realized under a particular condition.

Incidentally, in addition to the first method, in the switching and linkage process of the encoder head by the second and third methods described above, the measurement value of another head to be newly used was predicted so that the position coordinate of wafer stage WST which is monitored is continuously linked before and after the switching, and this predicted value was set as an initial value for the measurement value of another head. Instead of the processing above, the measurement error of another head including the measurement error generated by the switching and linkage process can be computed and the correction data can be made. And, while the another head is being used, the correction data that has been made can be used for servo drive control of wafer stage WST.

In this case, based on the correction data, positional information of wafer stage WST measured by the another head can be corrected, or a target position of wafer stage WST for servo control can be corrected. Furthermore, in the exposure operation, servo drive control of the reticle stage is performed, following the movement of wafer stage WST. Therefore, based on the correction data, instead of correcting the servo control of wafer stage WST, the follow-up servo control of the reticle stage can be corrected. Further, according to these control methods, the measurement value of the head before the switching may be set as an initial value of another head without any changes. Incidentally, when making the correction data, not only the encoder system but also other measurement systems that the exposure apparatus in the embodiment has, such as the interferometer systems, should be appropriately used.

Next, a parallel processing operation that uses wafer stage WST and measurement stage MST in exposure apparatus 100 of the embodiment will be described based on FIGS. 22 to 35. Incidentally, during the operation below, main controller 20 performs the open/close control of each valve of liquid supply device 5 and liquid recovery device 6 of local liquid immersion device 8 in the manner previously described, and water is constantly filled in the space right under tip lens 191 of projection optical system PL. However, in the description below, for the sake of simplicity, the explanation related to the control of liquid supply device 5 and liquid recovery device 6 will be omitted. Further, many drawings are used in the operation description hereinafter, however, reference

codes may or may not be given to the same member for each drawing. More specifically, the reference codes written are different for each drawing, however, such members have the same configuration, regardless of the indication of the reference
5 codes. The same can be said for each drawing used in the description so far.

FIG. 22 shows a state where exposure by the step-and-scan method is being performed on wafer W (in this case, as an example, the wafer is a wafer midway of a certain lot (one
10 lot contains 25 or 50 wafers)) on wafer stage WST. In this state, measurement stage MST can wait at a withdrawal position where it avoids bumping into wafer stage WST, however, in the embodiment, measurement stage MST is moving, following wafer stage WST while keeping a predetermined distance. Therefore,
15 when measurement stage MST moves into a contact state (or a proximity state) with wafer stage WST after the exposure has been completed, the same distance as the predetermined distance referred to above will be enough to cover the movement distance of measurement stage MST.

20 During this exposure, main controller 20 controls the position (including the θ_z rotation) of wafer table WTB (wafer stage WST) within the XY plane, based on the measurement values of at least three encoders out of two X heads 66 (X encoders 70B and 70D) shown surrounded by a circle in FIG. 22 facing
25 X scales 39X₁ and 39X₂, respectively, and two Y heads 64 (Y encoders 70A and 70C) shown surrounded by a circle in FIG. 22 facing Y scales 39Y₁ and 39Y₂, respectively, the pitching amount or rolling amount, and yawing amount of wafer stage WST measured by interferometer system 118, the stage position

induced error correction information (correction information obtained by formula (10) or formula (11) previously described) of each encoder corresponding to the Z position, the correction information of the grating pitch of each scale and correction information of the warp of the grid line. Further, main controller 20 controls the position of wafer table WTB in the Z-axis direction, the θ_y rotation (rolling), and the θ_x rotation (pitching), based on measurement values of one pair each of Z sensors $74_{1,j}$ and $74_{2,j}$, and $76_{1,q}$ and $76_{2,q}$ that face one end and the other end (in the embodiment, Y scales $39Y_1$ and $39Y_2$) of the wafer table WTB surface in the X-axis direction. Incidentally, the position of wafer table WTB in the Z-axis direction and the θ_y rotation (rolling) can be controlled based on the measurement value of Z sensors $74_{1,j}$, $74_{2,j}$, $76_{1,q}$, and $76_{2,q}$, and the θ_x rotation (pitching) can be controlled based on the measurement values of Y interferometer 16. In any case, the control (focus leveling control of wafer W) of the position of wafer table WTB in the Z-axis direction, the θ_y rotation, and the θ_x rotation during this exposure is performed, based on results of a focus mapping performed in advance by the multipoint AF system previously described.

Main controller 20 performs the exposure operation described above, based on results of wafer alignment (e. g. Enhanced Global Alignment (EGA)) that has been performed beforehand and on the latest baseline and the like of alignment systems AL_1 , and AL_{2_1} to AL_{2_4} , by repeating a movement operation between shots in which wafer stage WST is moved to a scanning starting position (an acceleration starting position) for exposure of each shot area on wafer W, and a scanning exposure

operation in which a pattern formed on reticle R is transferred onto each shot area by a scanning exposure method.

Incidentally, the exposure operation described above is performed in a state where water is retained in the space
5 between tip lens 191 and wafer W. Further, exposure is performed in the order from the shot area located on the -Y side to the shot area located on the + Y side in FIG. 22. Incidentally, details on the EGA method are disclosed, for example, in U.S. Patent No. 4,780,617 and the like.

10 And before the last shot area on wafer W is exposed, main controller 20 controls stage drive system 124 based on the measurement value of Y interferometer 18 while maintaining the measurement value of X interferometer 130 to a constant value, and moves measurement stage MST (measurement table MTB)
15 to the position shown in FIG. 23. When the measurement stage is moved, the edge surface of CD bar 46 (measurement table MTB) on the - Y side touches the edge surface of wafer table WTB on the +Y side. Incidentally, measurement table MTB and wafer table WTB can be separated, for example, at around 300 μ m
20 in the Y-axis direction while monitoring, for example, the measurement values of the interferometer or the encoder that measures the position of each table in the Y-axis direction so as to maintain a non-contact state (proximity state). After wafer stage WST and measurement stage MST are set to
25 the positional relation shown in FIG. 23 during the exposure of wafer W, both stages are moved while maintaining this positional relation.

Subsequently, as shown in FIG. 24, main controller 20 begins the operation of driving measurement stage MST in the

- Y-direction, and also begins the operation of driving wafer stage WST toward unloading position UP, while maintaining the positional relation of wafer table WTB and measurement table MTB in the Y-axis direction. When the operations begin, in
5 the embodiment, measurement stage MST is moved only in the -Y-direction, and wafer stage WST is moved in the -Y-direction and the -X-direction.

When main controller 20 simultaneously drives wafer stage WST and measurement stage MST in the manner described
10 above, the water (water of liquid immersion area 14 shown in FIG. 24) which was retained in the space between tip lens 191 of projection unit PU and wafer W sequentially moves over wafer W → plate 28 → CD bar 46 → measurement table MTB, along with the movement of wafer stage WST and measurement stage MST to
15 the - Y side. Incidentally, during the movement above, wafer table WTB and measurement table MTB maintain the contact state (or proximity state) previously described. Incidentally, FIG. 24 shows a state just before the water of liquid immersion area 14 is moved over to CD bar 46 from plate 28. Further,
20 in the state shown in FIG. 24, main controller 20 controls the position (including the θ_z rotation) of wafer table WTB (wafer stage WST) within the XY plane, based on the measurement values (and the stage position induced error correction information, the correction information of the grating pitch
25 of the scale and the correction information of the grid line of encoders 70A, 70B or 70D stored in memory 34, corresponding to the pitching amount, rolling amount, yawing amount, and the Z position of wafer stage WST measured by interferometer system 118) of the three encoders 70A, 70B, and 70D.

When wafer stage WST and measurement stage MST are driven simultaneously, slightly in the directions above furthermore from the state shown in FIG. 24, respectively, because the position measurement of wafer stage WST (wafer table WTB) by Y encoder 70A (and, 70C) will no longer be possible, main controller 20 switches the control of the Y position and the θ_z rotation of wafer stage WST (wafer table WTB) just before this, from a control based on the measurement values of Y encoders 70A and 70C to a control based on the measurement values of Y interferometer 16 and Z interferometers 43A and 43B. Then, after a predetermined time later, measurement stage MST reaches a position where baseline measurement (hereinafter appropriately referred to as Sec-BCHK (interval)) of the secondary alignment system is performed at a predetermined interval (in this case, at each wafer exchange) as shown in FIG. 25. Then, main controller 20 stops measurement stage MST at the position, and drives wafer stage WST furthermore toward unloading position UP and then stops wafer stage WST at unloading position UP, while measuring the X position of wafer stage WST using X head 66 (X linear encoder 70B) shown in FIG. 25 surrounded by a circle that faces X scale 39X₁ and also measuring the position in the Y-axis direction and the θ_z rotation and the like using Y interferometer 16 and Z interferometers 43A and 43B. Incidentally, in the state shown in FIG. 25, the water is retained in the space between measurement table MTB and tip lens 191.

Subsequently, as shown in FIGS. 25 and 26, main controller 20 adjusts the θ_z rotation of CD bar 46, based on the measurement values of Y-axis linear encoders 70E and 70F

configured by Y heads $64y_1$ and $64y_2$ shown in FIG. 26 surrounded by a circle that face a pair of reference gratings 52 on CD bar 46 supported by measurement stage MST, respectively, and also adjusts the XY position of CD bar 46, based on the measurement value of primary alignment system AL1 which detects reference mark M located on or in the vicinity of center line CL of measurement table MTB. Then, in this state, main controller 20 performs the Sec-BCHK (interval) in which the baseline (the relative position of the four secondary alignment systems with respect to primary alignment system AL1) of the four secondary alignment systems AL2₁ to AL2₄ is obtained by simultaneously measuring reference mark M on CD bar 46 located within the field of each secondary alignment system, respectively, using the four secondary alignment systems AL2₁ to AL2₄. In parallel with this Sec-BCHK (interval), main controller 20 gives a command to a drive system of an unload arm (not shown) so that wafer W on wafer stage WST suspended at unload position UP is unloaded, and also drives wafer stage WST in the +X-direction so that the stage is moved to loading position LP, while keeping a vertical movement pin CT (not shown in FIG. 25, refer to FIG. 26) elevated by a predetermined amount, which was driven upward on the unloading.

Next, as shown in FIG. 27, main controller 20 moves measurement stage MST to an optimal waiting position (hereinafter referred to as "optimal scrum waiting position"), which is the optimal waiting position for moving measurement stage MST from the state distanced from wafer stage WST into the contact state (or proximity state) previously described

with wafer stage WST. In parallel with this, main controller 20 gives a command to a drive system of a load arm (not shown) so that a new wafer W is loaded on wafer table WTB. In this case, because vertical movement pin CT is maintaining the state of being elevated by a predetermined amount, wafer loading can be performed in a short period of time when compared with the case when vertical movement pin CT is driven downward and is housed inside the wafer holder. Incidentally, FIG. 27 shows a state where wafer W is loaded on wafer table WTB.

10 In the embodiment, the optimal scrub waiting position of measurement stage MST referred to above is appropriately set according to the Y-coordinate of alignment marks arranged on the alignment shot area on the wafer. Further, in the embodiment, the optimal scrub waiting position is decided so that wafer stage WST can move into the contact state (or proximity state) at the position where wafer stage WST stops for wafer alignment.

Next, as shown in FIG. 28, main controller 20 moves wafer stage WST from loading position LP, to a position (more specifically, a position where the former process of base line measurement (Pri-BCHK) of the primary alignment system is performed) where fiducial mark FM on measurement plate 30 is positioned in the field (detection area) of primary alignment system AL1. During this movement, main controller 20 switches the control of position of wafer table WTB within the XY plane, from the control previously described based on measurement values of encoder 70B for the X-axis direction, Y interferometer 16 and Z interferometers 43A and 43B for the Y-axis direction and the θ_z rotation, to a control based on

the measurement values of at least three encoders, which are at least one of two X heads 66 (X encoders 70B and 70D) shown surrounded by a circle in FIG. 28 facing X scales 39X₁ and 39X₂, respectively, and two Y heads 64y₂ and 64y₁ (Y encoders 70A and 70C) shown surrounded by a circle in FIG. 28 facing Y scales 39Y₁ and 39Y₂, respectively, the stage position induced error correction information (correction information obtained by formula (10) or formula (11) previously described) of each encoder corresponding to the pitching amount or rolling amount, and yawing amount and the Z position of wafer stage WST measured by interferometer system 118, the correction information of the grating pitch of each scale and correction information of the warp of the grid line.

Then, main controller 20 performs the former process of Pri-BCHK in which fiducial mark FM is detected using primary alignment system AL1. At this point in time, measurement stage MST is waiting at the optimal scrub waiting position described above.

Next, while controlling the position of wafer stage WST based on the measurement values of at least the three encoders and each correction information described above, main controller 20 begins the movement of wafer stage WST in the +Y-direction toward a position where the alignment marks arranged in three first alignment shot areas are detected.

Then, when wafer stage WST reaches the position shown in FIG. 29, main controller 20 stops wafer stage WST. Prior to this, main controller 20 activates (turns on) Z sensors 72a to 72d at the point when Z sensors 72a to 72d begins to move over wafer table WTB or at the point before, and measures

the Z position and the inclination (θ_y rotation and θ_x rotation) of wafer table WTB.

After wafer stage WST is stopped as in the description above, main controller 20 detects the alignment marks arranged
5 in the three first alignment shot areas substantially at the same time and also individually (refer to the star-shaped marks in FIG. 29), using primary alignment system AL1, and secondary alignment systems AL2₂ and AL2₃, and makes a link between the detection results of the three alignment systems AL1, AL2₂,
10 and AL2₃ and the measurement values (measurement values after the correction according to each correction information) of at least the three encoders above at the time of the detection, and stores them in the internal memory.

As in the description above, in the embodiment, the shift
15 to the contact state (or proximity state) between measurement stage MST and wafer stage WST is completed at the position where detection of the alignment marks of the first alignment shot areas is performed, and from this position, main controller 20 begins to move both stages WST and MST in the
20 +Y-direction (step movement toward the position for detecting alignment marks arranged in five second alignment shot areas) in the contact state (or proximity state). Prior to starting the movement of both stages WST and MST in the +Y-direction, as shown in FIG. 29, main controller 20 begins irradiation
25 of a detection beam from irradiation system 90a of the multipoint AF system (90a, 90b) toward wafer table WTB. Accordingly, a detection area of the multipoint AF system is formed on wafer table WTB.

Then, when both stages WST and MST reach the position

shown in FIG. 30 during the movement of both stages WST and MST in the +Y-direction described above, main controller 20 performs the former process of the focus calibration, and obtains the relation between the measurement values (surface position information on one side and the other side of wafer table WTB in the X-axis direction) of Z sensors 72a, 72b, 72c, and 72d, in a state where a straight line (center line) in the Y-axis direction passing through the center of wafer table WTB (substantially coinciding with the center of wafer W) coincides with straight line LV previously described, and the detection results (surface position information) of a detection point (the detection point located in or around the center, among a plurality of detection points) on the surface of measurement plate 30 of the multipoint AF system (90a, 90b). At this point, liquid immersion area 14 is located in the vicinity of the border of CD bar 46 and wafer table WTB. More specifically, liquid immersion area 14 is in a state just before it is passed over to wafer table WTB from CD bar 46.

Then, when both stages WST and MST move further in the +Y-direction while maintaining the contact state (or proximity state), and reach the position shown in FIG. 31, the alignment marks arranged in the five second alignment shot areas are detected substantially at the same time as well as individually (refer to the star-shaped marks in FIG. 31), using the five alignment systems AL1, and AL2₁ to AL2₄ and a link is made between the detection results of the five alignment systems AL1, and AL2₁ to AL2₄ and the measurement values (measurement values after the correction according to each correction information) of the three encoders 70A, 70C, and

70D at the time of the detection, and stored in the internal memory. At this point in time, since the X head that faces X scale 39X₁ and is located on straight line LV in the Y-axis direction, which passes through the optical axis of projection optical system PL does not exist, main controller 20 controls the position within the XY plane of wafer table WTB based on the measurement values of X head 66 facing X scale 39X₂ (X linear encoder 70D) and Y linear encoders 70A and 70C.

As is described above, in the embodiment, the positional information (two-dimensional positional information) of a total of eight alignment marks can be detected at the point when the detection of the alignment marks in the second alignment shot areas is completed. Therefore, at this stage, by using the positional information, main controller 20 can perform a statistical computation such as the one disclosed in, for example, Kokai (Japanese Unexamined Patent Application Publication) No. 61-44429 (the corresponding U.S. Patent No. 4,780,617) and the like, to obtain the scaling (shot magnification) of wafer W, and can adjust the optical properties of projection optical system PL, such as for example, the projection magnification, by controlling an adjustment device 68 (refer to FIG. 6) based on the shot magnification which has been computed. Adjustment device 68 adjusts the optical properties of projection optical system PL, for example, by driving a particular movable lens that configures projection optical system PL, or changing gas pressure in an airtight chamber formed between particular lenses that configure projection optical system PL or the like.

Further, after the simultaneous detection of the

alignment marks arranged in the five second alignment shot areas is completed, main controller 20 starts again movement in the +Y-direction of both stages WST and MST in the contact state (or proximity state), and at the same time, starts the
5 focus mapping using Z sensors 72a to 72d and the multipoint AF system (90a, 90b) simultaneously, as is shown in FIG. 31.

Then, when both stages WST and MST reach the position with which measurement plate 30 is located directly below projection optical system PL shown in FIG. 32, main controller
10 20 performs the Pri-BCHK latter process and the focus calibration latter process. In this case, the Pri-BCHK latter process refers to a processing in which a projected image (aerial image) of a pair of measurement marks on reticle R projected by projection optical system PL is measured, using
15 aerial image measuring device 45 previously described which has aerial image measurement slit pattern SL formed on measurement plate 30, and the measurement results (aerial image intensity depending on the XY position of wafer table WTB) are stored in the internal memory. In this processing,
20 the projected image of the pair of measurement marks is measured in an aerial image measurement operation by the slit scan method, using a pair of aerial image measurement slit patterns SL, similar to the method disclosed in, U.S. Patent Application Publication No. 2002/0041377 and the like.
25 Further, the focus calibration latter process refers to a processing in which main controller 20 measures the aerial image of a measurement mark formed on a mark plate (not shown) on reticle R or on reticle stage RST using aerial image measuring device 45, while controlling the position

(Z-position) of measurement plate 30 (wafer table WTB) related to the optical axis direction of projection optical system PL, based on the surface position information of wafer table WTB (wafer stage WST) measured by Z sensors 72a, 72b, 72c, and 72d, and then measures the best focus position of projection optical system PL based on the measurement results, as shown in FIG. 32. The measurement operation of the projected image of the measurement mark is disclosed in, for example, the pamphlet of International Publication No. WO 2005/124834 and the like. While moving measurement plate 30 in the Z-axis direction, main controller 20 takes in the measurement values of Z sensors 74_{1,4}, 74_{2,4}, 76_{1,3}, and 76_{2,3} in synchronization with taking in the output signal from aerial image measuring device 45. Then, main controller 20 stores the values of Z sensors 74_{1,4}, 74_{2,4}, 76_{1,3}, and 76_{2,3} corresponding to the best focus position of projection optical system PL in a memory (not shown). Incidentally, the reason why the position (Z position) related to the optical axis direction of projection optical system PL of measurement plate 30 (wafer stage WST) is controlled using the surface position information measured in the focus calibration latter process by Z sensors 72a, 72b, 72c, and 72d is because the focus calibration latter process is performed during the focus mapping previously described.

In this case, because liquid immersion area 14 is formed between projection optical system PL and measurement plate 30 (wafer table WTB), the measurement of the aerial image described above is performed via projection optical system PL and water Lq. Further, because measurement plate 30 and

the like are installed in wafer stage WST (wafer table WTB), and the light receiving element and the like are installed in measurement stage MST, the measurement of the aerial image described above is performed while maintaining the contact
5 state (or proximity state) of wafer stage WST and measurement stage MST, as shown in FIG. 32. By the measurement described above, measurement values (more specifically, surface position information of wafer table WTB) of Z sensors 74_{1,4}, 74_{2,4}, 76_{1,3}, and 76_{2,3} corresponding to the best focus position
10 of projection optical system PL are obtained, in a state where the straight line (the center line) in the Y-axis direction passing through the center of wafer table WTB coincides with straight line LV previously described.

Then, main controller 20 computes the baseline of
15 primary alignment system AL1, based on the results of the Pri-BCHK former process and the results of the Pri-BCHK latter process described above. With this, based on the relation between the measurement values (surface position information of wafer table WTB) of Z sensors 72a, 72b, 72c, and 72d obtained
20 in the focus calibration former process described above and the detection results (surface position information) of the detection point on the surface of measurement plate 30 of the multipoint AF system (90a, 90b), and the measurement values (more specifically, surface position information of wafer
25 table WTB) of Z sensors 74_{1,4}, 74_{2,4}, 76_{1,3}, and 76_{2,3} corresponding to the best focus position of projection optical system PL which are obtained in the focus calibration latter process described above, main controller 20 obtains the offset at a representative detection point (in this case, the

detection point located in or around the center, among a plurality of detection points) of the multipoint AF system (90a, 90b) with respect to the best focus position of projection optical system PL and adjusts the detection origin of the multipoint AF system, for example, by an optical method so that the offset becomes zero.

In this case, from the viewpoint of improving throughput, only one processing of the Pri-BCHK latter process described above and the focus calibration latter process can be performed, or the procedure can move on to the next processing without performing both processing. As a matter of course, in the case the Pri-BCHK latter process is not performed, the Pri-BCHK former process described earlier also does not have to be performed, and in this case, main controller 20 only has to move wafer stage WST from loading position LP described earlier to a position where the alignment marks arranged in the first alignment shot areas are detected. Incidentally, in the case Pri-BCHK process is not performed, the baseline which is measured by a similar operation just before the exposure of a wafer exposed earlier than wafer W subject to exposure is used. Further, when the focus calibration latter process is not performed, similar to the baseline, the best focus position of projection optical system PL which is measured just before the exposure of a preceding wafer is used.

Incidentally, in the state shown in FIG. 32, the focus mapping previously described is being continued.

When wafer stage WST reaches the position shown in FIG. 33 after a predetermined time by movement in the +Y-direction of both stages WST and MST in the contact state (or proximity

state) described above, main controller 20 stops wafer stage WST at that position, while also making measurement stage MST continue the movement in the +Y-direction. Then, main controller 20 almost simultaneously and individually detects
5 the alignment marks arranged in the five third alignment shot areas (refer to star-shaped marks in FIG. 33) using five alignment systems AL1 and AL2₁ to AL2₄, links the detection results of five alignment systems AL1 and AL2₁ to AL2₄ and the measurement values of at least three encoders (measurement
10 values after correction by each of the correction information) described previously out of the four encoders at the time of the detection and stores them in the internal memory. At this point in time, the focus mapping is being continued.

Meanwhile, after a predetermined period of time from the
15 suspension of wafer stage WST described above, measurement stage MST and wafer stage WST moves from the contact state (or proximity state) into a separation state. After moving into the separation state, main controller 20 stops the movement of measurement stage MST when measurement stage MST
20 reaches an exposure start waiting position where measurement stage MST waits until exposure is started.

Next, main controller 20 starts to move wafer stage WST in the +Y-direction toward a position where alignment marks arranged in three fourth alignment shot areas are detected.
25 At this point in time, the focus mapping is being continued. Meanwhile, measurement stage MST is waiting at the exposure start waiting position described above.

Then, when wafer stage WST reaches the position shown in FIG. 34, main controller 20 immediately stops wafer stage

WST, and almost simultaneously and individually detects the alignment marks arranged in the three fourth alignment shot areas on wafer W (refer to star-shaped marks in FIG. 34) using primary alignment system AL1 and secondary alignment systems AL2₂ and AL2₃, links the detection results of three alignment systems AL1, AL2₂ and AL2₃ and the measurement values of at least three encoders (measurement values after correction by the correction information) out of the four encoders at the time of the detection, and stores them in the internal memory. Also at this point in time, the focus mapping is being continued, and measurement stage MST is still waiting at the exposure start waiting position. Then, using the detection results of a total of 16 alignment marks and the measurement values (measurement values after the correction by each correction information) of the corresponding encoders obtained in the manner described above, main controller 20 computes array information (coordinate values) of all the shot areas on wafer W on a coordinate system (for example, an XY coordinate system whose origin is placed at the center of wafer table WTB) that is set by the measurement axes of the four encoders, using the EGA method disclosed in, for example, U.S. Patent No. 4,780,617 and the like.

Next, main controller 20 continues the focus mapping while moving wafer stage WST in the +Y-direction again. Then, when the detection beam from the multipoint AF system (90a, 90b) begins to miss the wafer W surface, as is shown in FIG. 35, main controller 20 ends the focus mapping. After that, based on the results of the wafer alignment (EGA) described earlier performed in advance, the latest baselines of the five

alignment systems AL1 and AL2₁ to AL2₄, and the like, main controller 20 performs exposure by the step-and-scan method in a liquid immersion exposure and sequentially transfers a reticle pattern to a plurality of shot areas on wafer W.

5 Afterwards, similar operations are repeatedly performed so as to expose the remaining wafers within the lot.

As is described in detail above, according to exposure apparatus 100 related to the embodiment, for example, while the lot is being processed, main controller 20 measures the
10 positional information (including the θ_z rotation) of wafer stage WST within the surface (the movement plane) parallel to the XY plane by three heads (encoders), which at least include one each of an X head (X encoder) and a Y head (Y encoder) of the encoder system. Then, based on the measurement results
15 of the positional information and the positional information ((X, Y) coordinate value) in the movement plane of the irradiation point of (the measurement beams outgoing from) the three heads used for measuring the positional information, main controller 20 drives wafer stage WST within the XY plane.
20 In this case, main controller 20 drives wafer stage WST within the XY plane, while computing the positional information of wafer stage WST within the XY plane using the affine transformation relation. Accordingly, it becomes possible to control the movement of wafer stage WST with good precision
25 while switching the head (encoder) used for control during the movement of wafer stage WST, using the encoder system including head units 62A to 62D which respectively have a plurality of Y heads 64 or a plurality of X heads 66.

Further, according to exposure apparatus 100 related to

the embodiment, prior to starting the lot processing in which wafer stage WST is driven, such as, for example, during the start-up of the apparatus, as one of a series of calibration of the encoder system that measures the positional information of wafer stage WST in the XY plane, the calibration process of the head position previously described is performed for each head. More specifically, for each head of the encoder system, main controller 20 acquires a measurement value (an X position or a Y position of wafer stage WST) of the head when rotating wafer stage WST at a predetermined angle θ in the XY plane and a measurement value of the rotation angle of wafer stage WST in the XY plane by interferometer system 118, and based on the measurement values and the rotation angle (θ) of each head that has been acquired, computes the positional information of the measurement beam emitted from the head in a direction orthogonal to the measurement direction. More specifically, for each of the plurality of Y heads (64, 64_{y1}, 64_{y2}) of the encoder system, main controller 20 computes the X positional information of the irradiation point of the measurement beam, and for each of the plurality of X heads 66, main controller 20 computes the Y positional information of the irradiation point of the measurement beam. Then, main controller 20 stores the information that has been computed, along with the design positional information related to the measurement direction of the irradiation point of the measurement beam for each head in memory 34.

And then, when driving wafer stage WST as is described above, main controller 20 uses the positional information in the direction orthogonal to the measurement direction of the

irradiation point of the measurement beam of each head and the design positional information in the measurement direction of the irradiation point of the measurement beam of each head stored in memory 34, and drives wafer stage WST within the XY plane while computing the positional information of wafer stage WST within the XY plane using the affine transformation relation.

Further, main controller 20 switches an encoder (a head) used for measuring the positional information of wafer stage WST in the XY plane from one of the encoders of the three encoders to another encoder, so that the position of wafer stage WST within the XY plane is maintained before and after the switching. Because of this, although the encoder which is used for the control of the position of wafer stage WST has been switched, the position of wafer stage WST within the XY plane is maintained before and after the switching, which makes an accurate linkage possible. Accordingly, it becomes possible to move wafer stage WST two-dimensionally, precisely along a predetermined course, while performing linkage between a plurality of encoders.

Further, according to exposure apparatus 100 of the embodiment, in the case of moving wafer stage WST in a predetermined direction, such as, for example, the Y-axis direction at the time of wafer alignment or exposure, wafer stage WST is driven in the Y-axis direction, based on the measurement information of the encoder system and the positional information (including inclination information, e. g., rotation information in the θ x direction) of wafer stage WST in a direction different from the Y-axis direction,

the characteristic information (e. g., the degree of flatness of the grating surface, and/or a grating formation error) of the scale. More specifically, wafer stage WST is driven to compensate for the measurement errors of the encoder system (encoders 70A and 70C) caused by the displacement (including the inclination) of wafer stage WST in a direction different from the Y-axis direction and the scale. In the embodiment, main controller 20 drives wafer stage WST in the Y-axis direction, based on the measurement values of encoders 70A and 70C that measure positional information of wafer stage WST in a predetermined direction, such as the Y-axis direction, the stage position induced error correction information (the correction information which is computed by formula (10) previously described) that corresponds to the positional information of wafer stage WST in a direction different (a direction besides the measurement direction) from the Y-axis direction at the time of measurement, for example, the positional information of wafer stage WST in the θ_x direction, the θ_z direction and the Z-axis direction measured by Y interferometer 16 and Z interferometer 43A and 43B of interferometer system 118, the correction information (the correction information which takes into consideration the unevenness (degree of flatness) of the Y scale) of the grating pitch of the Y scale, and the correction information of the warp of grid line 38 of the Y scale. In the manner described above, stage drive system 124 is controlled, based on the measurement values of encoders 70A and 70C whose measurement errors of encoders 70A and 70C due to the relative displacement of scales 39Y₁ and 39Y₂ and Y head 64 in the direction besides

the measurement direction, the grating pitch of Y scales 39Y₁ and 39Y₂, and the warp of grid line 38 have been corrected by each of correction information, and wafer stage WST is driven in the Y-axis direction. In this case, the count values of encoders 70A and 70C are substantially the same results as when an ideal grating (diffraction grating) is measured with an ideal encoder (head). An ideal grating (diffraction grating), here, refers to a grating whose surface of the grating is parallel to the movement plane (the surface parallel to the XY plane) of the stage and is a completely flat surface, and the pitch direction of the grating is parallel to the beam of the interferometer and the distance between the grid lines is completely equal. An ideal encoder (head) refers to an encoder (head) whose optical axis is perpendicular to the movement plane (and the XY plane) of the stage and whose count values do not change by Z displacement, leveling, yawing and the like.

Further, in the case wafer stage WST is moved in the X-axis direction, wafer stage WST is driven in the X-axis direction, based on the measurement information of the encoder system, the positional information (including inclination information, e. g., rotation information in the θ_y direction) of wafer stage WST in a direction different from the X-axis direction, and the characteristic information (e. g., the degree of flatness of the grating surface, and/or a grating formation error) of the scale. More specifically, wafer stage WST is driven to compensate for the measurement errors of the encoder system (encoders 70B and 70D) caused by the displacement (including the inclination) of wafer stage WST

in a direction different from the X-axis direction. In the embodiment, main controller 20 drives wafer stage WST in the X-axis direction, based on the measurement values of encoders 70B and 70D which measure the positional information of wafer stage WST in the X-axis direction, the positional information of wafer stage WST in a direction different from the X-axis direction at the time of the measurement (non-measurement direction), such as, for example, the stage position induced error correction information (the correction information which is computed by formula (11) previously described) that corresponds to the positional information of wafer stage WST in the θ_y direction, θ_z direction, and the Z-axis direction measured by Z interferometers 43A and 43B of interferometer system 118, the correction information (the correction information which takes into consideration the unevenness (degree of flatness) of the X scales) of the grating pitch of the X scales, and the correction information of the warp of grid line 37 of the X scales. In the manner described above, stage drive system 124 is controlled, based on the measurement values of encoders 70B and 70D whose measurement errors of encoders 70B and 70D due to the relative displacement of scales 39X₁ and 39X₂ and X head 66 in the direction besides the measurement direction, the grating pitch of X scales 39X₁ and 39X₂, and the warp of grid line 37 have been corrected by each of correction information, and wafer stage WST is driven in the X-axis direction. In this case, the count values of encoders 70B and 70D are substantially the same results as when an ideal grating (diffraction grating) is measured with an ideal encoder (head).

Accordingly, it becomes possible to drive wafer stage WST using an encoder in a desired direction with good precision, without being affected by the relative motion in directions other than the direction (measurement direction) of the head and the scale to be measured, without being affected by the unevenness of the scale, and without being affected by the grating pitch of the scale and the grating warp.

Further, according to exposure apparatus 100 of the embodiment, for relative movement between illumination light IL irradiated on wafer W via reticle R, projection optical system PL, and wafer Lq from illumination system 10 and wafer W, main controller 20 drives wafer stage WST on which wafer W is placed with good precision, based on the measurement values of each encoder described above, the stage position induced error correction information of each encoder corresponding to the positional information of the wafer stage in the non-measurement direction at the time of the measurement, and the correction information of the grating pitch of each scale and the correction information of the grid line.

Accordingly, by scanning exposure and liquid immersion exposure, it becomes possible to form a desired pattern of reticle R in each shot area on the wafer with good precision.

Further, in the embodiment, as it has been described earlier based on FIGS. 28 and 29, prior to the measurement (EGA alignment measurement) of the alignment marks arranged in the three first alignment shot areas on wafer W by alignment systems AL₁, AL₂, and AL₃, main controller 20 switches the measurement device used for the position control of wafer stage WST from interferometer system 118 to the encoder system

(switches the control of the position of wafer table WTB within the XY plane from the irregular control previously described to the control based on the measurement values of at least three encoders out of encoders 70B and 70D and encoders 70A and 70C). According to this, even if there are some errors in the measurement values of the X position and the Y position of wafer stage WST by the encoder system just after the switching, there is an advantage of the errors being consequently canceled by the EGA performed next.

Further, according to the embodiment, on acquiring the stage position induced error correction information of the measurement values of the encoder previously described, main controller 20 changes wafer stage WST into a plurality of different attitudes, and for each attitude, in a state where the attitude of wafer stage WST is maintained based on the measurement results of interferometer system 118, moves wafer stage WST in the Z-axis direction in a predetermined stroke range while irradiating a detection light from head 64 or 66 of the encoder on the specific area of scales 39Y₁, 39Y₂, 39X₁ or 39X₂, and samples the measurement results of the encoder during the movement. According to this, change information (for example, an error characteristics curve as shown in the graph in FIG. 12) of the measurement values of the encoder corresponding to the position in the direction (Z-axis direction) orthogonal to the movement plane of wafer stage WST for each attitude can be obtained.

Then, by performing a predetermined operation based on this sampling result, namely the change information of the measurement values of the encoder corresponding to the

position of wafer stage WST in the Z-axis direction for each attitude, main controller 20 obtains the correction information of the measurement values of the encoder corresponding to the positional information of wafer stage WST in the non-measurement direction. Accordingly, the stage position induced error correction information for correcting the measurement errors of the encoder due to a relative change between the head and the scale in the non-measurement direction can be determined by a simple method.

10 Further, in the embodiment, in the case of deciding the correction information above, for a plurality of heads that configure the same head unit, such as, for example, a plurality of Y heads 64 that configure head unit 62A, a detection light is irradiated from each Y head 64 on the same specific area
15 of the corresponding Y scale 39Y₁ and a sampling is performed on the measurement results of the encoder described above, and because the correction information of each encoder configured by each Y head 64 and Y scale 39Y₁ is decided based on the sampling result, by using this correction information,
20 a geometric error which occurs because of the gradient of the head can also be consequently corrected. In other words, when main controller 20 obtains the correction information with the plurality of encoders corresponding to the same scale as the object, it obtains the correction information of the
25 encoder serving as the object taking into consideration the geometric error which occurs by the gradient of the head of the object encoder when wafer stage WST is moved in the Z-axis direction. Accordingly, in the embodiment, a cosine error caused by different gradient angles in a plurality of heads

is also not generated. Further, even if a gradient does not occur in Y head 64, for example, when a measurement error occurs in an encoder caused by the optical properties (telecentricity) of the head or the like, obtaining the correction information similarly can prevent the measurement error from occurring, which in turn prevents the deterioration of the position control precision of wafer stage WST. That is, in the embodiment, wafer stage WST is driven so as to compensate for the measurement errors (hereinafter also referred to as a head induced error) of the encoder system which occur due to the head unit. Incidentally, for example, correction information of the measurement values of the encoder system can be computed, based on the characteristic information (for example, including the slant of the head and/or the optical properties and the like) of the head unit.

Incidentally in the embodiment above, the case has been described where main controller 20 measures the positional information (including the θ_z rotation) of wafer stage WST in the surface (movement plane) parallel to the XY plane using three heads (an encoder) of the encoder system, and the position of wafer stage WST in the XY plane is controlled, based on a measurement result of the positional information and positional information ((X, Y) coordinate value) of the three heads (the irradiation point of the measurement beam) in the movement plane used for measuring the positional information, however, the present invention is not limited to this. For example, in the case when a movable body is not allowed to rotate within the movement plane, the degree of freedom that the movable body has is only two degrees of freedom

(X, Y) in the movement plane, however, the present invention can be applied even to such a case. That is, even in such a case, when the position of the movable body in the movement plane (the surface parallel to the XY plane) is controlled
5 using an encoder, by using the accurate positional information as positional information of each head in the movement plane, a highly precise position control becomes possible.

Incidentally, in the embodiment above, the measurement values of the encoder system were corrected based on the
10 correction information previously described so as to compensate for the measurement error due to the position of the detection point of the head or the positional shift of the head, however, the present invention is not limited to this, and, for example, the target position to which wafer stage WST is to be positioned can be corrected based on the
15 correction information, while driving wafer stage WST based on the measurement values of the encoder system. Or, especially in the exposure operation, the position of reticle stage RST can be corrected based on the correction information
20 previously described, while, for example, driving wafer stage WST based on the measurement values of the encoder system.

Further, in the embodiment above, as the positional information of the detection point of the head, the position in the direction besides the measurement direction or the
25 positional shift amount from the design value is obtained, however, in the measurement from the second time onward, the amount of change (that is, the positional shift from the previous measurement value) of the position of the detection point of the measurement this time from the position of the

detection point from the previous measurement can be obtained. Further, in the embodiment above, when performing the switching and the linkage process of the head previously described, as the positional information of the detection point of the head, the actual measurement value was used for the direction besides the measurement direction and the design value was used for the measurement direction, however, the present invention is not limited to this, and the position of the head can also be actually measured for the measurement direction, and in such a case, the positional information which was actually measured can be used instead of the design value previously described. The positional information of the detection point of the head which was actually measured can be used in a process besides the linkage process, such as, for example, the correction of the encoder measurement value.

Incidentally, in the embodiment above, when the wafer stage is moved in the X-axis direction, for example, the switching of the head and linkage process of head unit 62A and head unit 62C is performed simultaneously, or a part of the process is performed in parallel, however, the process can be performed in head units 62A and 62C at a different timing. In this case, for example, the distance between adjacent heads is to be the same in head units 62A and 62C, and the position of head units 62A and 62C placed in the X-axis direction can be shifted.

Incidentally, in the embodiment above, an invention related to the switching of the head of the encoder and the linkage of the measurement value, an invention related to the correction of various measurement errors (e. g., head position

induced error, stage position induced error, head induced error, scale induced error and the like) of the encoder system, an invention (invention about the reset of the encoder system) in which the position control of the wafer stage using the encoder system was started once more after every wafer exchange, an invention related to the switching timing in which the switching operation of the encoder (head) is executed at a timing in synchronization with the position control of the wafer stage, an invention to prepare the schedule for the switching timing based on the movement course of the wafer stage and the like were carried out by the same exposure apparatus. However, these inventions can be executed alone or in any combination.

Further, one or a combination of two or more of the stage position induced error, head induced error (the measurement error of the encoder system that occurs not by the head position but due to the head unit as in the inclination of the head or the optical properties (such as telecentricity)), and the scale induced error can be performed, combined with the correction of the head position induced error.

Incidentally, in each of the embodiments above, in order to simplify the description, main controller 20 had control over each part of the exposure apparatus such as the stage system and the like, however, the present invention is not limited to this, and it is a matter of course that at least a part of the control performed by main controller 20 can be shared with a plurality of controllers. For example, a stage controller, which controls wafer stage WST based on the measurement values of the encoder system, the Z sensor and

the interferometer system, can be arranged to operate under main controller 20. Further, the control that main controller 20 performs does not necessarily have to be realized by hardware, and the control can be realized by software using a computer program that sets the operation of main controller 20 or each operation of some controllers that share the control as previously described.

Incidentally, the configuration and the placement of the encoder system, the interferometer system, the multipoint AF system, the Z sensor and the like in the embodiment above is an example among many, and it is a matter of course that the present invention is not limited to this. For example, in the embodiment above, an example was indicated of a case where the pair of Y scales 39Y₁ and 39Y₂ used for the measurement of the position in the Y-axis direction and the pair of X scales 39X₁ and 39X₂ used for the measurement of the position in the X-axis direction are arranged on wafer table WTB, and corresponding to the scales, the pair of head units 62A and 62C is placed on one side and the other side of the X-axis direction of projection optical system PL, and the pair of head units 62B and 62D is placed on one side and the other side of the Y-axis direction of projection optical system PL. However, the present invention is not limited to this, and of Y scales 39Y₁ and 39Y₂ used for the measurement of the position in the Y-axis direction and X scales 39X₁ and 39X₂ used for the measurement of the position in the X-axis direction, at least one of the scales can be arranged singularly on wafer table WTB, without being a pair, or, of the pair of head units 62A and 62C and the pair of head units

62B and 62D, at least one of the head units can be arranged, singularly. Further, the extension direction of the scale and the extension direction of the head unit are not limited to an orthogonal direction such as the X-axis direction and the Y-axis direction in the embodiment above, and it can be any direction as long as the directions intersect each other. Further, the periodic direction of the diffraction grating can be a direction orthogonal to (or intersecting with) the longitudinal direction of each scale, and in such a case, a plurality of heads of the corresponding head unit should be placed in a direction orthogonal to the periodic direction of the diffraction grating. Further, each head unit can have a plurality of heads placed without any gap in a direction orthogonal to the periodic direction of the diffraction grating.

Further, in the embodiment above, the case has been described where the grating section (the X scale and the Y scale) was placed on a surface of wafer stage WST parallel to the XY plane, or to be more specific, on the upper surface, however, the present invention is not limited to this, and the grating can be placed as a matter of course on the lower surface of wafer stage WST, as well as the side surface, or a head can be arranged on the movable body side such as the wafer stage, and the a grating (a two-dimensional grating or a one-dimensional grating section placed two-dimensionally) can be placed external to the movable body. In this case, when a Z sensor is also placed on the upper surface of the movable body, the grating externally placed can also be used as a reflection surface that reflects the measurement beam from

the Z sensor.

Incidentally, in the embodiment above, rotation information (pitching amount) of wafer stage WST in the θ_x direction was measured by interferometer system 118, however, for example, the pitching amount can be obtained from the measurement values of either of the pair of Z sensors 74_{i,j} or 76_{p,q}. Or, similar to head units 62A and 62C, for example, one Z sensor or a pair of Z sensors can be arranged in proximity to each head of head units 62B and 62D, and the pitching amount can be obtained from X scales 39X₁ and 39X₂ and the measurement value of the Z sensors that face the scales, respectively. Accordingly, it becomes possible to measure the positional information of wafer stage WST in directions of six degrees of freedom, or more specifically, the X-axis, Y-axis, Z-axis, θ_x , θ_y , and θ_z directions using the encoder and the Z sensor previously described, without using interferometer system 118. The measurement of the positional information of wafer stage WST in directions of six degrees of freedom using the encoder and the Z sensor previously described can be performed not only in the exposure operation but also in the alignment operation and/or the focus mapping operation previously described.

Further, in the embodiment above, wafer stage WST was driven based on the measurement value of the encoder system, for example, in the case of exposure, however, for example, an encoder system that measures the position of reticle stage RST can be added, and reticle stage RST can be driven based on the correction information that corresponds to the measurement values of the encoder system and the positional

information of the reticle stage in the non-measurement direction measured by reticle interferometer 116.

Further, in the embodiment above, the case has been described where the apparatus is equipped with one fixed
5 primary alignment system and four movable secondary alignment systems, and alignment marks arranged in the 16 alignment shot areas on the wafer are detected by the sequence according to the five alignment systems. However, the secondary alignment system does not need to be movable, and, further, the number
10 of the secondary alignment systems does not matter. The important thing is that there is at least one alignment system that can detect the alignment marks on the wafer.

Incidentally, in the embodiment above, the exposure apparatus which is equipped with measurement stage MST
15 separately from wafer stage WST was described as in the exposure apparatus disclosed in the pamphlet of International Publication No. WO 2005/074014, however, the present invention is not limited to this, and for example, as is disclosed in, for example, Kokai (Japanese Patent Unexamined
20 Application Publication) No. 10-214783 and the corresponding U.S. Patent No. 6,341,007, and in the pamphlet of International Publication No. WO 98/40791 and the corresponding U.S. Patent No. 6,262,796 and the like, even in an exposure apparatus by the twin wafer stage method that can execute the exposure
25 operation and the measurement operation (e. g., mark detection by the alignment system) almost in parallel using two wafer stages, it is possible to perform the position control of each wafer stage using the encoder system (refer to FIG.3 and the like) previously described. By appropriately setting the

placement and length of each head unit not only during the exposure operation but also during the measurement operation, the position control of each wafer stage can be performed continuing the use of the encoder system previously described, however, a head unit that can be used during the measurement operation can be arranged, separately from the head units (62A to 62D) previously described. For example, four head units can be placed in the shape of a cross with one or two alignment systems in the center, and during the measurement operation above, the positional information of each wafer stage WST can be measured using these head units and the corresponding scales. In the exposure apparatus by the twin wafer stage method, at least two scales each are arranged in the two wafer stages, respectively, and when the exposure operation of the wafer mounted on one of the wafer stages is completed, in exchange with the stage, the other wafer stage on which the next wafer that has undergone mark detection and the like at the measurement position is mounted is placed at the exposure position. Further, the measurement operation performed in parallel with the exposure operation is not limited to the mark detection of wafers and the like by the alignment system, and instead of this, or in combination with this, the surface information (step information) of the wafer can also be detected.

Incidentally, in the embodiment above, the case has been described where Sec-BCHK (interval) is performed using CD bar 46 on the measurement stage MST side while each wafer is exchanged on the wafer stage WST side, however, the present invention is not limited to this, and at least one of an

illuminance irregularity measurement (and illuminance measurement), aerial image measurement, wavefront aberration measurement and the like can be performed using a measuring instrument (measurement member) of measurement stage MST, and
5 the measurement results can be reflected in the exposure of the wafer performed later on. To be more concrete, for example, projection optical system PL can be adjusted by adjustment device 68 based on the measurement results.

Further, in the embodiment above, a scale can also be
10 placed on measurement stage MST, and the position control of the measurement stage can be performed using the encoder system (head unit) previously described. More specifically, the movable body that performs the measurement of positional information using the encoder system is not limited to the
15 wafer stage.

Incidentally, when reducing the size and weight of wafer stage WST is taken into consideration, it is desirable to place the scale as close as possible to wafer W on wafer stage WST, however, when the size of the wafer stage is allowed to increase,
20 by increasing the size of the wafer stage and increasing the distance between the pair of scales that is placed facing each other, positional information of at least two each in the X-axis and Y-axis directions, that is, a total of four positional information, can be measured constantly during the
25 exposure operation of the wafer. Further, instead of increasing the size of the wafer stage, for example, a part of the scale can be arranged so that it protrudes from the wafer stage, or, by placing the scale on the outer side of wafer stage main body using an auxiliary plate on which at

least one scale is arranged, the distance between the pair of facing scales can be increased as in the description above.

Further, in the embodiment above, in order to prevent deterioration in the measurement accuracy caused by adhesion of a foreign material, contamination, and the like to Y scales 39Y₁ and 39Y₂, and X scales 39X₁ and 39X₂, for example, a coating can be applied on the surface so as to cover at least the diffraction grating, or a cover glass can be arranged. In this case, especially in the case of a liquid immersion type exposure apparatus, a liquid repellent protection film can be coated on the scale (a grating surface), or a liquid repellent film can be formed on the surface (upper surface) of the cover glass. Furthermore, the diffraction grating was formed continually on substantially the entire area in the longitudinal direction of each scale, however, for example, the diffraction grating can be formed intermittently divided into a plurality of areas, or each scale can be configured by a plurality of scales. Further, in the embodiment above, an example was given in the case where an encoder by the diffraction interference method is used as the encoder, however, the present invention is not limited to this, and methods such as the so-called pickup method, the magnetic method and the like can be used, and the so-called scan encoders whose details are disclosed in, for example, U.S. Patent No. 6,639,686 and the like, can also be used.

Further, in the embodiment above, as the Z sensor, instead of the sensor by the optical pick-up method referred to above, for example, a sensor configured by a first sensor (the sensor can be a sensor by the optical pick-up method or

other optical displacement sensors) that irradiates a probe beam on a measurement object surface and optically reads the displacement of the measurement object surface in the Z-axis direction by receiving the reflected light, a drive section
5 that drives the first sensor in the Z-axis direction, and a second sensor (e. g. an encoder and the like) that measures the displacement of the first sensor in the Z-axis direction can be used. In the Z sensor having the configuration described above, a mode (the first servo control mode) in which
10 the drive section drives the first sensor in the Z-axis direction based on the output of the first sensor so that the distance between the measurement object surface, such as the surface of the scale and the first sensor in the Z-axis direction is always constant, and a mode (the second servo
15 control mode) in which a target value of the second sensor is given from an external section (controller) and the drive section maintains the position of the first sensor in the Z-axis direction so that the measurement values of the second sensor coincides with the target value can be set. In the case
20 of the first servo control mode, as the output of the Z sensor, the output of the measuring section (the second sensor) can be used, and in the case of the second servo control mode, the output of the second sensor can be used. Further, in the case of using such a Z sensor, and an encoder is employed as
25 the second sensor, as a consequence, the positional information of wafer stage WST (wafer table WTB) in directions of six degrees of freedom can be measured using an encoder. Further, in the embodiment above, as the Z sensor, a sensor by other detection methods can be employed.

Further, in the embodiment above, the configuration of the plurality of interferometers used for measuring the positional information of wafer stage WST and their combination are not limited to the configuration and the combination previously described. The important thing is that as long as the positional information of wafer stage WST in the direction except for the measurement direction of the encoder system can be measured, the configuration of the interferometers and their combination does not especially matter. The important thing is that there should be a measurement device (it does not matter whether it is an interferometer or not) besides the encoder system described above that can measure the positional information of wafer stage WST in the direction except for the measurement direction of the encoder system. For example, the Z sensor previously described can be used as such measurement device.

Further, in the embodiment above, the Z sensor was arranged besides the multipoint AF system, however, for example, as long as the surface position information of the shot area subject to exposure of wafer W can be detected with the multipoint AF system on exposure, then the Z sensor does not necessarily have to be arranged.

Incidentally, in the embodiment above, pure water (water) was used as the liquid, however, it is a matter of course that the present invention is not limited to this. As the liquid, liquid that is chemically stable, having high transmittance to illumination light IL and safe to use, such as a fluorine-containing inert liquid may be used. As the fluorine-containing inert liquid, for example, Fluorinert

(the brand name of 3M United States) can be used. The fluorine-containing inert liquid is also excellent from the point of cooling effect. Further, as the liquid, liquid which has a refractive index with respect to illumination light IL higher than pure water (a refractive index is around 1.44), for example, liquid having a refractive index equal to or higher than 1.5 can be used. As this type of liquid, for example, a predetermined liquid having C-H binding or O-H binding such as isopropanol having a refractive index of about 1.50, glycerol (glycerin) having a refractive index of about 1.61, a predetermined liquid (organic solvent) such as hexane, heptane or decane, or decalin (decahydronaphthalene) having a refractive index of about 1.60, or the like can be cited. Alternatively, a liquid obtained by mixing arbitrary two or more of these liquids may be used, or a liquid obtained by adding (mixing) the predetermined liquid described above to (with) pure water can be used. Alternatively, as the liquid, a liquid obtained by adding (mixing) base or acid such as H^+ , Cs^+ , K^+ , Cl^- , SO_4^{2-} , or PO_4^{2-} to (with) pure water can be used. Moreover, a liquid obtained by adding (mixing) particles of Al oxide or the like to (with) pure water can be used. These liquids can transmit ArF excimer laser light. Further, as the liquid, liquid, which has a small absorption coefficient of light, is less temperature-dependent, and is stable to a projection optical system (tip optical member) and/or a photosensitive agent (or a protection film (top coat film), an antireflection film, or the like) coated on the surface of a wafer, is preferable. Further, in the case an F_2 laser is used as the light source, fomblin oil can be selected.

Further, in the embodiment above, the recovered liquid may be reused, and in this case, a filter that removes impurities from the recovered liquid is preferably arranged in a liquid recovery device, a recovery pipe or the like.

5 Further, in the embodiment above, the case has been described where the exposure apparatus is a liquid immersion type exposure apparatus, however, the present invention is not limited to this, and it can also be applied to a dry type exposure apparatus that performs exposure of wafer W without
10 liquid (water).

Further, in the embodiment above, the case has been described where the present invention is applied to a scanning exposure apparatus by a step-and-scan method or the like. However, the present invention is not limited to this, but
15 may also be applied to a static exposure apparatus such as a stepper. Even with the stepper or the like, by measuring the position of a stage on which an object subject to exposure is mounted by encoders, generation of position measurement error caused by air fluctuations can substantially be nulled
20 likewise. Furthermore, even with the stepper, it becomes possible to set the position of the stage with high precision based on the measurement values of the encoder and each correction information previously described, and as a consequence, it becomes possible to transfer a reticle pattern
25 onto an object with high precision. Further, the present invention can also be applied to a reduction projection exposure apparatus by a step-and-stitch method that synthesizes a shot area and a shot area, an exposure apparatus by a proximity method, a mirror projection aligner, or the

like.

Further, the magnification of the projection optical system in the exposure apparatus of the embodiment above is not only a reduction system, but can also be either an equal
5 magnifying system or a magnifying system, and projection optical system PL is not only a dioptric system, but can also be either a catoptric system or a catadioptric system, and in addition, the projected image may be either an inverted image or an upright image. Moreover, the exposure area to
10 which illumination light IL is irradiated via projection optical system PL is an on-axis area that includes optical axis AX within the field of projection optical system PL. However, for example, as is disclosed in the pamphlet of International Publication No. WO 2004/107011, the exposure
15 area can also be an off-axis area that does not include optical axis AX, similar to a so-called inline type catadioptric system, in a part of which an optical system (catoptric system or catadioptric system) that has plural reflection surfaces and forms an intermediate image at least once is arranged, and
20 which has a single optical axis. Further, the illumination area and exposure area described above are to have a rectangular shape. However, the shape is not limited to rectangular, and can also be circular arc, trapezoidal, parallelogram or the like.

25 Further, the light source of the exposure apparatus in the embodiment above is not limited to the ArF excimer laser, and a pulsed laser light source such as a KrF excimer laser (output wavelength 248 nm), an F₂ laser (output wavelength 157 nm), an Ar₂ laser (output wavelength 126 nm), or a Kr₂ laser

(output wavelength 146 nm), or an ultra high-pressure mercury lamp that generates a bright line such as the g-line (wavelength 436 nm) or the i-line (wavelength 365 nm) can also be used as the light source. Further, a harmonic wave
5 generating device of a YAG laser or the like can also be used. Besides the sources above, as is disclosed in, for example, the pamphlet of International Publication No. WO 1999/46835 (the corresponding U.S. Patent No. 7,023,610), a harmonic wave, which is obtained by amplifying a single-wavelength laser beam
10 in the infrared or visible range emitted by a DFB semiconductor laser or fiber laser as vacuum ultraviolet light, with a fiber amplifier doped with, for example, erbium (or both erbium and ytterbium), and by converting the wavelength into ultraviolet light using a nonlinear optical crystal, can also
15 be used.

Further, in the embodiment above, illumination light IL of the exposure apparatus is not limited to the light having a wavelength equal to or more than 100nm, and it is needless to say that the light having a wavelength less than 100nm can
20 be used. For example, in recent years, in order to expose a pattern equal to or less than 70nm, development of an EUV exposure apparatus that makes an SOR or a plasma laser as a light source generate an EUV (Extreme Ultraviolet) light in a soft X-ray range (e.g. a wavelength range from 5 to 15 nm),
25 and uses a total reflection reduction optical system designed under the exposure wavelength (e.g. 13.5nm) and the reflective mask is underway. In the EUV exposure apparatus, the arrangement in which scanning exposure is performed by synchronously scanning a mask and a wafer using a circular

arc illumination can be considered, and therefore, the present invention can also be suitably applied to such an exposure apparatus. Besides such an apparatus, the present invention can also be applied to an exposure apparatus that uses charged
5 particle beams such as an electron beam or an ion beam.

Further, in the embodiment above, a transmissive type mask (reticle), which is a transmissive substrate on which a predetermined light shielding pattern (or a phase pattern or a light attenuation pattern) is formed, is used. Instead
10 of this reticle, however, as is disclosed in, for example, U.S. Patent No. 6,778,257, an electron mask (which is also called a variable shaped mask, an active mask or an image generator, and includes, for example, a DMD (Digital Micromirror Device) that is a type of a non-emission type image
15 display device (spatial light modulator) or the like) on which a light-transmitting pattern, a reflection pattern, or an emission pattern is formed according to electronic data of the pattern that is to be exposed can also be used. In the case of using such a variable shaped mask, because the stage
20 on which a wafer or a glass plate is mounted moves relatively with respect to the variable shaped mask, by driving the stage based on the measurement values of an encoder and each correction information previously described while measuring the position of the stage using the encoder system and
25 performing the linkage operation between a plurality of encoders previously described, an equivalent effect as the embodiment described above can be obtained.

Further, as is disclosed in, for example, the pamphlet of International Publication No. WO 2001/035168, the present

invention can also be applied to an exposure apparatus (lithography system) that forms line-and-space patterns on a wafer by forming interference fringes on the wafer.

Moreover, the present invention can also be applied to
5 an exposure apparatus that synthesizes two reticle patterns on a wafer via a projection optical system and almost simultaneously performs double exposure of one shot area on the wafer by one scanning exposure, as is disclosed in, for example, Kohyo (published Japanese translation of
10 International Publication for Patent Application) No. 2004-519850 (the corresponding U.S. Patent No. 6,611,316).

Further, an apparatus that forms a pattern on an object is not limited to the exposure apparatus (lithography system) described above, and for example, the present invention can
15 also be applied to an apparatus that forms a pattern on an object by an ink-jet method.

Incidentally, an object on which a pattern is to be formed (an object subject to exposure to which an energy beam is irradiated) in the embodiment above is not limited to a
20 wafer, and can be other objects such as a glass plate, a ceramic substrate, a film member, or a mask blank.

The use of the exposure apparatus is not limited only to the exposure apparatus for manufacturing semiconductor devices, but the present invention can also be widely applied
25 to an exposure apparatus for transferring a liquid crystal display device pattern onto a rectangular glass plate and an exposure apparatus for producing organic ELs, thin-film magnetic heads, imaging devices (such as CCDs), micromachines, DNA chips, and the like. Further, the present invention can

be applied not only to an exposure apparatus for producing microdevices such as semiconductor devices, but can also be applied to an exposure apparatus that transfers a circuit pattern onto a glass plate or silicon wafer to produce a reticle
5 or mask used in a light exposure apparatus, an EUV exposure apparatus, an X-ray exposure apparatus, an electron-beam exposure apparatus, and the like.

Incidentally, the movable body drive system, the movable body drive method, or the deciding method of the present
10 invention can be applied not only to the exposure apparatus, but can also be applied widely to other substrate processing apparatuses (such as a laser repair apparatus, a substrate inspection apparatus and the like), or to apparatuses equipped with a movable body such as a stage that moves within a
15 two-dimensional plane such as a position setting apparatus for specimen or a wire bonding apparatus in other precision machines.

Further, the exposure apparatus (the pattern formation apparatus) of the embodiment above is manufactured by
20 assembling various subsystems, which include the respective constituents that are recited in the claims of the present application, so as to keep predetermined mechanical accuracy, electrical accuracy and optical accuracy. In order to secure these various kinds of accuracy, before and after the assembly,
25 adjustment to achieve the optical accuracy for various optical systems, adjustment to achieve the mechanical accuracy for various mechanical systems, and adjustment to achieve the electrical accuracy for various electric systems are performed. A process of assembling various subsystems into

the exposure apparatus includes mechanical connection, wiring connection of electric circuits, piping connection of pressure circuits, and the like among various types of subsystems. Needless to say, an assembly process of individual subsystem is performed before the process of assembling the various subsystems into the exposure apparatus. When the process of assembling the various subsystems into the exposure apparatus is completed, a total adjustment is performed and various kinds of accuracy as the entire exposure apparatus are secured. Incidentally, the making of the exposure apparatus is preferably performed in a clean room where the temperature, the degree of cleanliness and the like are controlled.

Incidentally, the disclosures of the various publications, the pamphlets of the International Publications, and the U.S. Patent Application Publication descriptions and the U.S. Patent descriptions that are cited in the embodiment above and related to exposure apparatuses and the like are each incorporated herein by reference.

Next, an embodiment of a device manufacturing method in which the exposure apparatus (pattern formation apparatus) described above is used in a lithography process will be described.

FIG. 36 shows a flowchart of an example when manufacturing a device (a semiconductor chip such as an IC or an LSI, a liquid crystal panel, a CCD, a thin film magnetic head, a micromachine, and the like). As is shown in FIG. 36, first of all, in step 201 (a design step), function and performance design of a device (such as circuit design of

semiconductor device) is performed, and pattern design to realize the function is performed. Then, in step 202 (a mask making step), a mask is made on which the circuit pattern that has been designed is formed. Meanwhile, in step 203 (a wafer
5 fabrication step), wafers are manufactured using materials such as silicon.

Next, in step 204 (a wafer processing step), the actual circuit and the like are formed on the wafer by lithography or the like in a manner that will be described later, using
10 the mask and the wafer prepared in steps 201 to 203. Then, in step 205 (a device assembly step), device assembly is performed using the wafer processed in step 204. Step 205 includes processes such as the dicing process, the bonding process, and the packaging process (chip encapsulation), and
15 the like when necessary.

Finally, in step 206 (an inspecting step), inspections such as the operation check test, the durability test and the like of a device made by step 205 are performed. After these processes, the devices are completed and are shipped out.

20 FIG. 37 is a flowchart showing a detailed example of step 204 described above in the case of semiconductor devices. In FIG. 37, in step 211 (an oxidation step), the surface of the wafer is oxidized. In step 212 (CDV step), an insulating film is formed on the wafer surface. In step 213 (an electrode
25 formation step), an electrode is formed on the wafer by deposition. In step 214 (an ion implantation step), ions are implanted into the wafer. Each of the above steps 211 to step 214 constitutes the preprocess in each step of wafer processing, and the necessary processing is chosen and is executed at each

stage.

When the above-described preprocess ends in each stage of wafer processing, post-process is executed as follows. First of all, in the post-process, first in step 215 (a resist formation step), a photosensitive agent is coated on the wafer. Then, in step 216 (an exposure step), the circuit pattern of the mask is transferred onto the wafer by the exposure apparatus (pattern formation apparatus) described above and the exposure method (pattern formation method) thereof. Next, in step 217 (a development step), the wafer that has been exposed is developed, and in step 218 (an etching step), an exposed member of an area other than the area where resist remains is removed by etching. Then, in step 219 (a resist removing step), when etching is completed, the resist that is no longer necessary is removed.

By repeatedly performing the pre-process and the post-process, multiple circuit patterns are formed on the wafer.

By using the device manufacturing method of the embodiment described above, because the exposure apparatus (pattern formation apparatus) in the embodiment above and the exposure method (pattern formation method) thereof are used in the exposure step (step 216), exposure with high throughput can be performed while maintaining the high overlay accuracy. Accordingly, the productivity of highly integrated microdevices on which fine patterns are formed can be improved.

INDUSTRIAL APPLICABILITY

As is described above, the movable body drive system and

the movable body drive method of the present invention are suitable for driving a movable body within a movement plane. Further, the pattern formation apparatus and the pattern formation method of the present invention are suitable for forming a pattern on an object. Further, the exposure apparatus, the exposure method and the device manufacturing method of the present invention are suitable for manufacturing micro devices. Further, the calibration method of an encoder of the present invention is suitable for calibration of the setting position of the head of the encoder.

CLAIMS

1. A movable body drive method in which a movable body is driven along a substantially predetermined plane, the
5 method comprising:

a drive process in which positional information of the movable body in a first direction is measured, using at least one first head of an encoder system that includes a plurality of first heads which irradiates a measurement beam on a grating
10 whose periodic direction is the first direction parallel to the plane and receives the beam from the grating and is arranged in a direction intersecting the first direction, and the movable body is driven along the plane, based on a measurement result of the positional information and positional
15 information in a surface parallel to the plane of the measurement beam emitted from at least one of the first heads used for the measurement of the positional information.

2. The movable body drive method according to Claim 1
20 wherein

the grating is placed on a surface of the movable body substantially parallel to the plane.

3. The movable body drive method according to Claim 2
25 wherein

on the surface of the movable body, a grating is placed furthermore whose periodic direction is a second direction that intersects the first direction and is parallel to the plane, and

the encoder system further includes a plurality of second heads which irradiates a measurement beam on the grating whose periodic direction is the second direction and receives the beam from the grating, and measures positional information
5 in the second direction of the movable body, whereby

in the drive process of the movable body, positional information of the movable body in the surface parallel to the plane is measured using the at least one first head and at least one second head, and the movable body is driven along
10 the plane, based on the measurement results and positional information of each measurement beam in the surface parallel to the plane emitted from the at least one first head and the at least one second head.

15 4. The movable body drive method according to any one of Claims 1 to 3 wherein

in the drive process of the movable body, the movable body is driven along the plane, while computing positional information of the movable body in the surface parallel to
20 the plane using the relations of the affine transformation based on a measurement value of at least the two heads of the encoder system and positional information of each measurement beam in the surface parallel to the plane emitted from these heads.

25

5. The movable body drive method according to any one of Claims 1 to 4, the method further comprising prior to the drive process:

a computing process in which based on a measurement value

of a measurement device that measures a rotation angle of the movable body in the surface parallel to the plane, the movable body is rotated at a predetermined angle in the surface parallel to the plane, and based on a measurement value of
5 each of the heads after the rotation and information of the predetermined angle measured by the measurement device, positional information of the measurement beam emitted from each of the heads used for position control of the movable body in a direction orthogonal to a measurement direction of
10 the measurement beam is computed.

6. The movable body drive method according to Claim 4 wherein

as the measurement device, an interferometer having a
15 plurality of measurement axes is used.

7. The movable body drive method according to one of Claims 5 and 6 wherein

in the drive process, as the positional information of
20 the measurement beams emitted from each of the heads, the positional information computed in the computing process is used as positional information for a direction orthogonal to a measurement direction of the measurement beam, and design positional information is used as positional information for
25 the measurement direction.

8. A pattern formation method, comprising:

a mount process in which an object is mounted on a movable body that can move in a movement plane; and

a drive process in which the movable body is driven by the movable body drive method according to any one of Claims 1 to 7, to form a pattern to the object.

5 9. A device manufacturing method including a pattern formation process wherein

in the pattern formation process, a pattern is formed on an object using the pattern formation method according to Claim 8.

10

10. An exposure method in which a pattern is formed on an object by an irradiation of an energy beam wherein

for relative movement of the energy beam and the object, a movable body on which the object is mounted is driven, using
15 the movable body drive method according to any one of Claims 1 to 7.

11. An exposure method of exposing an object with an energy beam, the method comprising:

20 mounting the object on a movable body that can move at least in a first and second direction orthogonal in a predetermined plane, and

controlling a position of the movable body in the predetermined plane, based on measurement information of an
25 encoder system, which has one of a grating section and a head unit arranged on a surface of the movable body where the object is mounted and the other also arranged facing the surface of the movable body and also measures positional information of the movable body in the predetermined plane with a head that

faces the grating section among a plurality of heads of the head unit, and positional information of a detection point of the head used for the measurement in a surface parallel to the predetermined plane.

5

12. The exposure method according to Claim 11 wherein the position of the movable body is controlled to compensate for the measurement error of the encoder system that occurs due to a position or displacement of the detection
10 point.

13. The exposure method according to one of Claims 11 and 12 wherein

positional information of the detection point includes
15 positional information in a direction orthogonal to a measurement direction of the positional information of the movable body by the head.

14. The exposure method according to Claim 13 wherein
20 the plurality of heads are placed apart in a direction orthogonal to the measurement direction, and in the encoder system, the head used for the measurement is switched according to the position of the movable body in the direction orthogonal to the measurement direction.

25

15. The exposure method according to any one of Claims 11 to 14 wherein

one of the measurement information of the encoder system and a target position where the movable body is positioned

is corrected, based on the positional information of the detection point.

16. The exposure method according to any one of Claims
5 11 to 15 wherein

the object is exposed by the energy beam via a mask, and at the time of the exposure, the position of the mask is controlled based on positional information of the detection point to compensate for the measurement error of the encoder
10 system that occurs due to the position or displacement of the detection point of the head, while driving the movable body based on the measurement information of the encoder system.

17. An exposure method of exposing an object with an
15 energy beam, the method comprising:

mounting the object on a movable body that can move at least in a first and second direction orthogonal in a predetermined plane;

measuring positional information of the movable body
20 using an encoder system, which has one of a grating section and a head unit arranged on a surface of the movable body where the object is held and the other is also arranged facing the surface of the movable body and measures positional
information of the movable body in the predetermined plane
25 with a head that faces the grating section among a plurality of heads of the head unit; and

controlling the position of the movable body in the predetermined plane, based on correction information to compensate for the measurement error of the encoder system

that occurs due to the position or displacement of the detection point of the head used for the measurement and measurement information of the encoder system.

5 18. The exposure method according to Claim 17 wherein
the correction information compensates for the
measurement error of the encoder system that occurs due to
a position or displacement of the detection point in a
direction orthogonal to the measurement direction of the
10 positional information of the movable body with the head.

19. The exposure method according to Claim 18 wherein
the plurality of heads are placed apart in a direction
orthogonal to the measurement direction, and in the encoder
15 system, the head used for the measurement is switched according
to the position of the movable body in the direction orthogonal
to the measurement direction.

20. The exposure method according to any one of Claims
20 17 to 19 wherein
positional information of the detection point of the
head is detected using a detection device, and
the correction information is decided, based on the
positional information that has been detected.

25

21. The exposure method according to Claim 20 wherein
the detection device includes a measurement device which
is different from the encoder system that measures positional
information of the movable body in the predetermined plane,

and positional information of the detection point is obtained using measurement information of the encoder system and the measurement device.

5 22. The exposure method according to any one of Claims 17 to 21 wherein

the correction information compensates for the measurement error of the encoder system that occurs due to at least one of the head unit and the grating section.

10

23. The exposure method according to Claim 22 wherein the correction information compensates for the measurement error of the encoder system that occurs due to at least optical properties of the head unit.

15

24. The exposure method according to one of Claims 22 and 23 wherein

the correction information compensates for the measurement error of the encoder system that occurs due to at least one of flatness and formation error of the grating section.

20

25. The exposure method according to any one of Claims 17 to 24 wherein

25 the correction information compensates for the measurement error of the encoder system that occurs due to displacement of the movable body in a direction that is different from the first and second directions on the measurement.

26. The exposure method according to Claim 25 wherein
the different direction includes at least one of a
direction orthogonal to the predetermined plane, a rotational
5 direction around an axis orthogonal to the predetermined plane,
and a rotational direction around an axis parallel to the
predetermined plane.

27. The exposure method according to any one of Claims
10 17 to 26 wherein

the correction information compensates for the
measurement error of the encoder system that occurs due to
inclination of the movable body to the predetermined plane.

28. The exposure method according to any one of Claims
15 17 to 27 wherein

in the encoder system, the head used for the measurement
is switched by a movement of the movable body, and

the correction information compensates for the
20 measurement error of the encoder system that occurs due to
displacement of the movable body in a direction that is
different from the first and second directions on the
switching.

29. The exposure method according to any one of Claims
25 17 to 27 wherein

in the encoder system, the head used for the measurement
is switched by a movement of the movable body, and
positional information which should be measured by a

head after the switching is decided, based on positional
information measured by a head before the switching and
positional information of movable body in a direction that
is different from the first and second directions on the
5 switching.

30. The exposure method according to Claim 29 wherein
positional information which should be measured by a
head after the switching is decided so that the position of
10 the movable body is maintained before and after the switching,
and the positional information that has been decided is set
as an initial value of positional information measured by the
head after the switching so that the positional information
of the movable body is continuously linked before and after
15 the switching.

31. The exposure method according to any one of Claims
28 to 30 wherein
the direction that is different from the first and second
20 directions on the switching includes the rotational direction
in the predetermined plane.

32. The exposure method according to any one of Claims
17 to 27 wherein
25 positional information of the movable body in the first
direction, the second direction, and in the rotational
direction in the predetermined plane is measured by at least
three heads that face the grating section among the plurality
of heads, and also by the movement of the movable body, the

three heads used for the measurement are switched to three heads which include at least one head different from the three heads, whereby

on the switching, positional information which should
5 be measured by at least one head among three heads after the switching which is different from the three heads before the switching is decided, based on positional information measured by the three heads before the switching.

10 33. The exposure method according to Claim 32 wherein positional information which should be measured by at least one head after the switching is decided so that the position of the movable body is maintained before and after the switching, and the positional information that has been
15 decided is set as an initial value of positional information measured by the at least one head after the switching so that the positional information of the movable body is continuously linked before and after the switching.

20 34. The exposure method according to one of Claims 32 and 33 wherein

the positional information which should be measured by at least one head after the switching is to be decided, using positional information in a plane parallel to the
25 predetermined plane of the detection point of each head before and after of switching.

35. The exposure method according to any one of Claims 28 to 34 wherein

the switching is performed in a state where the head before the switching and the head after the switching both face the grating section.

5 36. The exposure method according to any one of Claims 17 to 35 wherein

one of the measurement information of the encoder system and a target position where the movable body is positioned is corrected, based on the correction information.

10

37. The exposure method according to any one of Claims 17 to 36 wherein

the object is exposed by the energy beam via a mask, and
at the time of the exposure, a position of the mask is
15 controlled based on the correction information so as to
compensate for the measurement error, while the movable body
is driven based on the measurement information of the encoder
system.

20 38. The exposure method according to any one of Claims 11 to 37 wherein

the grating section is arranged with a measurement
direction of the positional information of the movable body
by the head serving as a longitudinal direction, and the head
25 unit has the plurality of heads placed apart in a direction
orthogonal to the measurement direction.

39. The exposure method according to any one of Claims 11 to 38 wherein

the grating section has a pair of first grating sections whose longitudinal direction are the first direction and is placed apart in the second direction and a pair of second grating sections whose longitudinal direction are the second
5 direction and is placed apart in the first direction, and

the head unit has a pair of first head units having a plurality of first heads placed apart in the second direction and also the first head facing the pair of the first grating sections on exposure and a pair of second head units having
10 a plurality of second heads placed apart in the first direction and also the second heads facing the pair of the second grating sections on exposure.

40. The exposure method according to any one of Claims
15 11 to 39 wherein

the grating section is arranged on a surface of the movable body, and the head unit is arranged facing the surface of the movable body.

20 41. The exposure method according to any one of Claims 11 to 40 wherein

a measurement system is further used, which measures positional information of the movable body in a third direction orthogonal to the predetermined plane by a sensor facing the
25 grating section of the plurality of sensors placed on the same side as the head unit, and a position of the movable body in the third direction is controlled based on measurement information of the measurement system.

42. The exposure method according to Claim 41 wherein
the measurement system measures the positional
information and inclination information in the third
direction of the movable body with a plurality of sensors that
5 face the grating section.

43. The exposure method according to one of Claims 41
and 42 wherein

of the positional information of the movable body in
10 directions of six degrees of freedom, positional information
in directions of three degrees of freedom including the first
direction, the second direction, and the rotational direction
in the predetermined plane is measured by the encoder system,
and positional information in directions of remaining three
15 degrees of freedom is measured by the measurement system.

44. The exposure method according to Claim 43 wherein
the position of the movable body in at least the exposure
operation is controlled, based on the positional information
20 measured in directions of six degrees of freedom.

45. The exposure method according to any one of Claims
41 to 44 wherein

in a measurement operation of a surface position
25 information of the object, in addition to the encoder system
and the measurement system, a position measuring device which
measures the positional information of the object in the third
direction is used.

46. The exposure method according to any one of Claims 41 to 45. the method further comprising:

preparing a mark detection system that detects a mark on the object, wherein

5 in a detection operation of the mark, the encoder system and the mark detection system are used.

47. The exposure method according to any one of Claims 41 to 46 wherein

10 to drive the movable body, the measurement information of the encoder system is used in an exposure operation, and the measurement information of an interferometer system that measures the positional information of the movable body in at least the first and second directions is used in an operation
15 that is different from the exposure operation.

48. The exposure method according to Claim 47 wherein in a detection operation of a mark and/or the surface position information of the object, the measurement

20 information of the encoder system is used.

49. The exposure method according to one of Claims 47 and 48 wherein

at least a part of the measurement information of the
25 interferometer system is used in the exposure operation.

50. A device manufacturing method including a lithography process wherein

in the lithography process, an exposure method according

to any one of Claims 11 to 49 is used to expose a sensitive object mounted on the movable body, and to form a pattern on the sensitive object.

5 51. A movable body drive system in which a movable body is driven along a substantially predetermined plane, the system comprising:

 a grating whose periodic direction is a first direction parallel to the plane;

10 an encoder system which includes a plurality of first heads that irradiates a measurement beam on the grating and receives the beam from the grating, arranged in a direction intersecting the first direction; and

 a controller which measures positional information of
15 the movable body in the first direction using at least one first head of the plurality of first heads and drives the movable body along the plane, based on the measurement result of the positional information and positional information of the measurement beam emitted from the at least one first head
20 used for measurement of the positional information in a surface parallel to the plane.

 52. The movable body drive system according to Claim 51 wherein

25 the grating is placed on a surface of the movable body substantially parallel to the plane.

 53. The movable body drive system according to Claim 52 wherein

on the surface of the movable body, a grating is placed furthermore whose periodic direction is a second direction that intersects the first direction and is parallel to the plane, and

5 the encoder system further includes a plurality of second heads which irradiates a measurement beam on the grating whose periodic direction is the second direction, receives the beam from the grating, and measures positional information in the second direction of the movable body, and whose position
10 is different in a direction intersecting the second direction in the surface parallel to the plane, whereby

 the controller measures positional information of the movable body in the surface parallel to the plane, using the at least one first head and at least one second head, and drives
15 the movable body along the plane, based on the measurement results and positional information of each measurement beam in the surface parallel to the plane emitted from the at least one first head and the at least one second head.

20 54. The movable body drive system according to Claim 52 wherein

 a plurality of measurement beams emitted from each of the plurality of second heads is arranged in a direction intersecting the second direction in the surface parallel to
25 the plane.

 55. The movable body drive system according to any one of Claims 51 to 54 wherein

 the controller drives the movable body along the plane,

while computing positional information of the movable body in the surface parallel to the plane using the relations of the affine transformation based on a measurement value of at least the two heads of the encoder system and positional
5 information of each of the measurement beam in the surface parallel to the plane emitted from the two heads.

56. The movable body drive system according to any one of Claims 51 to 55, the system further comprising:

10 a measurement device which measures a rotation angle of the movable body in the movement plane; and

a processing device that rotates the movable body at a predetermined angle in the surface parallel to the plane based on a measurement value of the measurement device, and based
15 on a measurement value of each of the heads after the rotation and information of the predetermined angle measured by the measurement device, computes positional information of the measurement beams emitted from each of the heads used for position control of the movable body in a direction orthogonal
20 to a measurement direction.

57. The movable body drive system according to Claim 56 wherein

the measurement device is an interferometer that has a
25 plurality of measurement axes.

58. The movable body drive system according to one of Claims 56 and 57, the system further comprising:

a storage device in which positional information in a

direction orthogonal to a measurement direction of a measurement beam emitted from each of the heads computed by the processing device and a design positional information in a measurement direction of a measurement beam emitted from each of the heads is stored.

59. A pattern formation apparatus, the apparatus comprising:

a movable body on which the object is mounted, and is movable in a movement plane holding the object; and

a movable body drive system according to any one of Claims 51 to 58 that drives the movable body to perform pattern formation to the object.

60. An exposure apparatus that forms a pattern on an object by an irradiation of an energy beam, the apparatus comprising:

a patterning device that irradiates the energy beam on the object; and

the movable body drive system according to any one of Claims 51 to 58, whereby

the movable body drive system drives the movable body on which the object is mounted for relative movement of the energy beam and the object.

61. An exposure apparatus that exposes an object with an energy beam, the apparatus comprising:

a movable body that holds the object and is movable at least in a first and second directions which are orthogonal

in a predetermined plane;

an encoder system in which one of a grating section and a head unit is arranged on a surface of the movable body where the object is held and the other is arranged facing the surface of the movable body, and positional information of the movable
5 body in the predetermined plane is measured by a head that faces the grating section of a plurality of heads of the head unit; and

a controller that controls a position of the movable body
10 in the predetermined plane, based on measurement information of the encoder system and positional information of a detection point of the head used for the measurement in a surface parallel to the predetermined plane.

15 62. The exposure apparatus according to Claim 61 wherein

the position of the movable body is controlled to compensate for the measurement error of the encoder system that occurs due to a position or displacement of the detection
20 point.

63. The exposure apparatus according to one of Claims 61 and 62 wherein

positional information of the detection point includes
25 positional information in a direction orthogonal to a measurement direction of the positional information of the movable body by the head.

64. The exposure apparatus according to Claim 63

wherein

the plurality of heads are placed apart in a direction orthogonal to the measurement direction, and in the encoder system, the head used for the measurement is switched according to the position of the movable body in the direction orthogonal to the measurement direction.

65. The exposure apparatus according to any one of Claims 61 to 64 wherein

one of the measurement information of the encoder system and a target position where the movable body is positioned is corrected, based on the positional information of the detection point.

66. The exposure apparatus according to any one of Claims 61 to 65 wherein

the object is exposed by the energy beam via a mask, and at the time of the exposure, the position of the mask is controlled based on positional information of the detection point to compensate for the measurement error of the encoder system that occurs due to the position or displacement of the detection point of the head, while driving the movable body based on the measurement information of the encoder system.

67. An exposure apparatus that exposes an object with an energy beam, the apparatus comprising:

a movable body that holds the object and is movable at least in a first and second directions which are orthogonal in a predetermined plane;

an encoder system in which one of a grating section and a head unit is arranged on a surface of the movable body where the object is held and the other is arranged facing the surface of the movable body, and positional information of the movable
5 body in the predetermined plane is measured by a head that faces the grating section of a plurality of heads of the head unit; and

a controller that controls the position of the movable body in the predetermined plane, based on correction
10 information to compensate for the measurement error of the encoder system that occurs due to the position or displacement of the detection point of the head used for the measurement and measurement information of the encoder system.

15 68. The exposure apparatus according to Claim 67 wherein

the correction information compensates for the measurement error of the encoder system that occurs due to a position or displacement of the detection point in a
20 direction orthogonal to the measurement direction of the positional information of the movable body with the head.

69. The exposure apparatus according to Claim 68 wherein

25 the plurality of heads are placed apart in a direction orthogonal to the measurement direction, and in the encoder system, the head used for the measurement is switched according to the position of the movable body in the direction orthogonal to the measurement direction.

70. The exposure apparatus according to any one of Claims 67 to 69, the apparatus further comprising:

a detection device that detects positional information
5 of a detection point of the head, and

the correction information is decided, based on the positional information that has been detected.

71. The exposure apparatus according to Claim 70
10 wherein

the detection device includes a measurement device which is different from the encoder system that measures positional information of the movable body in the predetermined plane, and positional information of the detection point is obtained
15 using measurement information of the encoder system and the measurement device.

72. The exposure apparatus according to any one of Claims 67 to 71 wherein

20 the correction information compensates for the measurement error of the encoder system that occurs due to at least one of the head unit and the grating section.

73. The exposure apparatus according to Claim 72
25 wherein

the correction information compensates for the measurement error of the encoder system that occurs due to at least optical properties of the head unit.

74. The exposure apparatus according to one of Claims 72 and 73 wherein

the correction information compensates for the measurement error of the encoder system that occurs due to
5 at least one of flatness and formation error of the grating section.

75. The exposure apparatus according to any one of Claims 67 to 74 wherein

10 the correction information compensates for the measurement error of the encoder system that occurs due to displacement of the movable body in a direction that is different from the first and second directions on the measurement.

15

76. The exposure apparatus according to Claim 75 wherein

the different direction includes at least one of a direction orthogonal to the predetermined plane, a rotational
20 direction around an axis orthogonal to the predetermined plane, and a rotational direction around an axis parallel to the predetermined plane.

77. The exposure apparatus according to any one of
25 Claims 67 to 76 wherein

the correction information compensates for the measurement error of the encoder system that occurs due to inclination of the movable body to the predetermined plane.

78. The exposure apparatus according to any one of Claims 67 to 77 wherein

in the encoder system, the head used for the measurement is switched by a movement of the movable body, and

5 the correction information compensates for the measurement error of the encoder system that occurs due to displacement of the movable body in a direction that is different from the first and second directions on the switching.

10

79. The exposure apparatus according to any one of Claims 67 to 77 wherein

in the encoder system, the head used for the measurement is switched by a movement of the movable body, and

15 positional information which should be measured by a head after the switching is decided, based on positional information measured by a head before the switching and positional information of movable body in a direction that is different from the first and second directions on the
20 switching.

80. The exposure apparatus according to Claim 79 wherein

positional information which should be measured by a
25 head after the switching is decided so that the position of the movable body is maintained before and after the switching, and the positional information that has been decided is set as an initial value of positional information measured by the head after the switching so that the positional information

of the movable body is continuously linked before and after the switching.

81. The exposure apparatus according to any one of
5 Claims 78 to 80 wherein

the direction that is different from the first and second directions on the switching includes the rotational direction in the predetermined plane.

10 82. The exposure apparatus according to any one of Claims 67 to 77 wherein

positional information of the movable body in the first direction, the second direction, and in the rotational direction in the predetermined plane is measured by at least
15 three heads that face the grating section among the plurality of heads, and also by the movement of the movable body, the three heads used for the measurement are switched to three heads which include at least one head different from the three heads, whereby

20 on the switching, positional information which should be measured by at least the one head among three heads after the switching which is different from the three heads before the switching is decided, based on positional information measured by the three heads before the switching.

25

83. The exposure apparatus according to Claim 82 wherein

positional information which should be measured by at least one head after the switching is decided so that the

position of the movable body is maintained before and after the switching, and the positional information that has been decided is set as an initial value of positional information measured by the at least one head after the switching so that
5 the positional information of the movable body is continuously linked before and after the switching.

84. The exposure apparatus according to one of Claims 82 and 83 wherein

10 the positional information which should be measured by at least one head after the switching is to be decided, using positional information in a plane parallel to the predetermined plane of the detection point of each head before and after the switching.

15

85. The exposure apparatus according to any one of Claims 78 to 84 wherein

the switching is performed in a state where the head before the switching and the head after the switching both
20 face the grating section.

86. The exposure apparatus according to any one of Claims 67 to 85 wherein

one of the measurement information of the encoder system
25 and a target position where the movable body is positioned is corrected, based on the correction information.

87. The exposure apparatus according to any one of Claims 67 to 86 wherein

the object is exposed by the energy beam via a mask, and at the time of the exposure, a position of the mask is controlled based on the correction information so as to compensate for the measurement error, while the movable body
5 is driven based on the measurement information of the encoder system.

88. The exposure apparatus according to any one of Claims 61 to 87 wherein

10 the grating section is arranged with a measurement direction of the positional information of the movable body by the head serving as a longitudinal direction, and the head unit has the plurality of heads placed apart in a direction orthogonal to the measurement direction.

15

89. The exposure apparatus according to any one of Claims 61 to 88 wherein

the grating section has a pair of first grating sections whose longitudinal direction is the first direction and are
20 placed apart in the second direction and a pair of second grating sections whose longitudinal direction is the second direction and is placed apart in the first direction, and the head unit has a pair of first head units having a plurality of first heads placed apart in the second direction and also
25 the first heads facing the pair of the first grating sections on exposure and a pair of second head units having a plurality of second heads placed apart in the first direction and also the second heads facing the pair of the second grating sections on exposure.

90. The exposure apparatus according to any one of Claims 61 to 89 wherein

the grating section is arranged on a surface of the
5 movable body, and the head unit is arranged facing the surface
of the movable body.

91. The exposure apparatus according to any one of Claims 61 to 90, the apparatus further comprising:

10 a measurement system which measures positional
information of the movable body in a third direction orthogonal
to the predetermined plane by a sensor facing the grating
section of the plurality of sensors placed on the same side
as the head unit, wherein

15 a position of the movable body in the third direction
is controlled, based on measurement information of the
measurement system.

92. The exposure apparatus according to Claim 91
20 wherein

the measurement system measures the positional
information in the third direction and inclination
information of the movable body with a plurality of sensors
that faces the grating section.

25

93. The exposure apparatus according to one of Claims 91 and 92 wherein

of the positional information of the movable body in
directions of six degrees of freedom, positional information

in directions of three degrees of freedom including the first direction, the second direction, and the rotational direction in the predetermined plane is measured by the encoder system, and positional information in directions of remaining three
5 degrees of freedom is measured by the measurement system.

94. The exposure apparatus according to Claim 93 wherein

the position of the movable body in at least the exposure
10 operation is controlled, based on the positional information measured in directions of six degrees of freedom.

95. The exposure apparatus according to any one of Claims 91 to 94, the apparatus further comprising:

15 a position measuring device that measures positional information of the object in the third direction, wherein in a measurement operation of a surface position information of the object, the encoder system, the measurement system, and the position measuring device are used.

20

96. The exposure apparatus according to any one of Claims 91 to 95, the apparatus further comprising:

a mark detection system that detects a mark on the object, wherein

25 in a detection operation of the mark, the encoder system and the mark detection system are used.

97. The exposure apparatus according to any one of Claims 91 to 96, the apparatus further comprising:

an interferometer system that measures positional information of the movable body in at least the first and second directions, wherein

to drive the movable body, the measurement information
5 of the encoder system is used in an exposure operation, and the measurement information of the interferometer system is used in an operation that is different from the exposure operation.

10 98. The exposure apparatus according to Claim 97 wherein

in a detection operation of a mark and/or the surface position information of the object, the measurement information of the encoder system is used.

15

99. The exposure apparatus according to one of Claims 97 and 98 wherein

at least a part of the measurement information of the interferometer system is used in the exposure operation.

20

100. A calibration method used in an encoder system that measures positional information of a movable body that moves along a substantially predetermined plane in a surface parallel to the plane, the method comprising:

25 an acquisition process in which the movable body is rotated at a predetermined angle in the surface parallel to the plane and a measurement value of a head of the encoder system that measures the positional information of the movable body in a measurement direction parallel to the plane and a

measurement value of a measurement device that measures a rotation angle of the movable body in the surface parallel to the plane are acquired; and

- 5 a computing process in which positional information of a measurement beam emitted from the head in a direction perpendicular to the measurement direction in the surface parallel to the plane is computed, based on the measurement value of the head that has been acquired and the rotation angle that has been measured by the measurement device.