

MEMS-Based Tuning Fork Gyroscope

[Zaman, Ayazi, et al, MEMS'06]

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MEMS-Based Tuning Fork Gyroscope

- Drive and sense axes must be stable or at least track one another to avoid output drift

Problem: if drive frequency changes relative to sense frequency, output changes \Rightarrow bias drift

Need: small or matched drive and sense axis temperature coefficients to suppress drift

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Mode Matching for Higher Resolution

- For higher resolution, can try to match drive and sense axis resonance frequencies and benefit from Q amplification

Problem: mismatch between drive and sense frequencies \Rightarrow even larger drift!

Need: small or matched drive and sense axis temperature coefficients to make this work

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Issue: Zero Rate Bias Error

- Imbalances in the system can lead to zero rate bias error

Mass imbalance \Rightarrow off-axis motion of the proof mass

Drive imbalance \Rightarrow off-axis motion of the proof mass

Output signal in phase with the Coriolis acceleration

Quadrature output signal that can be confused with the Coriolis acceleration

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Nuclear Magnetic Res. Gyroscope

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- The ultimate in miniaturized spinning gyroscopes?
 ↳ from CSAC, we may now have the technology to do this

-20°
0°
20°

Better if this is a noble gas nucleus (rather than e-), since nuclei are heavier ⇒ less susceptible to B field

Soln: Spin polarize Xe¹²⁹ nuclei by first polarizing e- of Rb⁸⁷ (a la CSAC), then allowing spin exchange

-20°
0°
20°

Atoms
Aligned Nuclear Spins

3.2 mm
1 mm
 $\dot{\theta}$

Challenge: suppressing the effects of B field

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MEMS-Based Tuning Fork Gyroscope

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Drive Voltage Signal

Sense

Drive

Drive Oscillation Sustaining Amplifier

Differential TransR Sense Amplifier

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