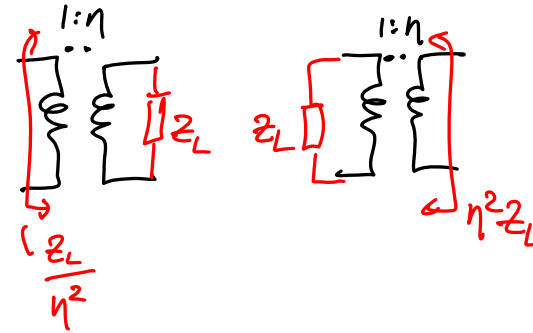


Lecture 25: Gyroscopes & Sensing Circuits

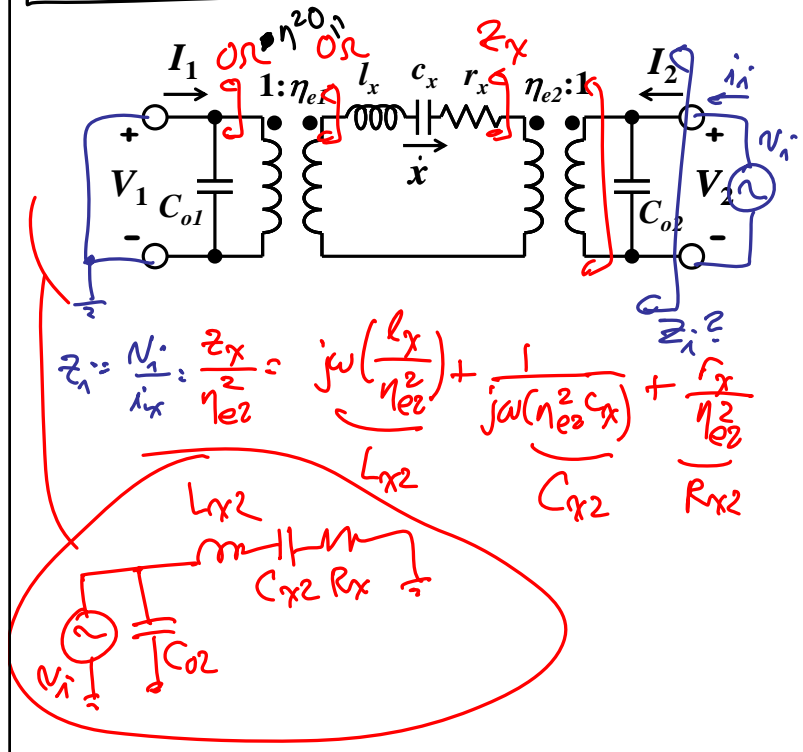
- Announcements:
- **Reminder:** 3rd project slide due Dec. 3
- **HW#7** has been online for a week & it's due on Thursday, Dec. 9
- **Project Outbrief Signups**
 - ↳ Monday, Dec. 13?
 - ↳ Friday, Dec. 10?
-
- **Reading:** Senturia, Chpt. 6, Chpt. 14
- **Lecture Topics:**
 - ↳ **Input Modeling**
 - Force-to-Velocity Equiv. Ckt.
 - Input Equivalent Ckt.
 - ↳ **Current Modeling**
 - Output Current Into Ground
 - Input Current
 - Complete Electrical-Port Equiv. Ckt.
 - ↳ **Impedance & Transfer Functions**
- **Reading:** Senturia, Chpt. 14, Chpt. 16, Chpt. 21
- **Lecture Topics:**
 - ↳ **Gyroscopes**
- **Reading:** Senturia, Chpt. 14
- **Lecture Topics:**
 - ↳ **Detection Circuits**
 - Velocity Sensing
 - Position Sensing
-
- **Last Time:**

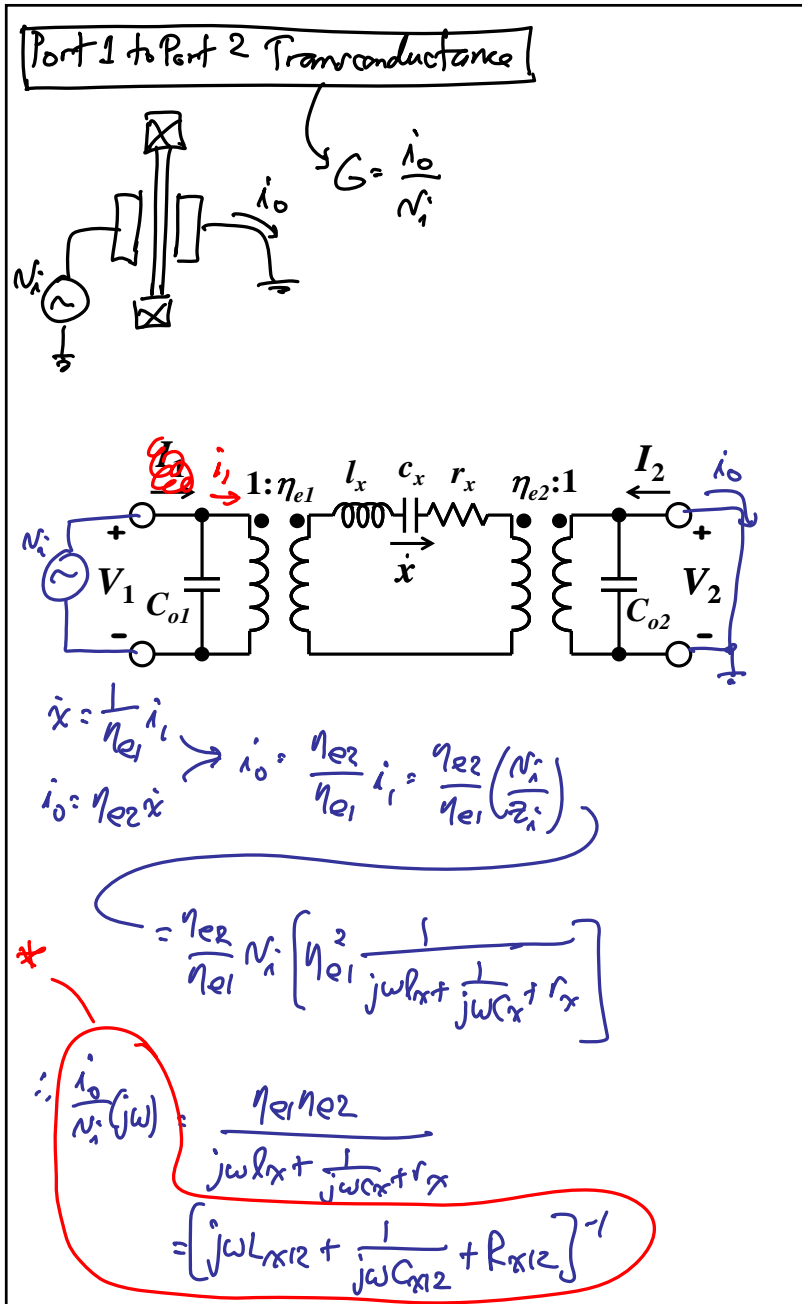


Transformer Impedance Analysis



Input Impedance Into Port 2





$L_{x12} = \frac{L_x}{\eta_{e1}\eta_{e2}}, C_{x12} = \eta_{e1}\eta_{e2}C_x, R_{x12} = \frac{r_x}{\eta_{e1}\eta_{e2}}$

Separate freq. response & magnitude:

* $\frac{i_o}{N_1}(s) = \frac{1}{sL_{x12} + \frac{1}{sC_{x12}} + R_{x12}} = \frac{s(\frac{1}{L_{x12}})}{s^2 + \frac{1}{L_{x12}C_{x12}} + s(\frac{R_{x12}}{L_{x12}})}$

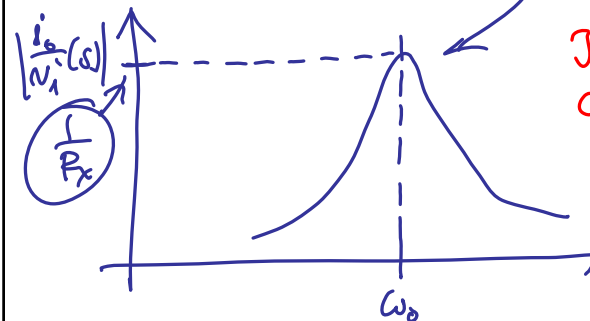
$\left[\frac{1}{L_{x12}C_{x12}} = \omega_0^2, Q = \frac{\omega_0 L_{x12}}{R_{x12}} \rightarrow \frac{R_{x12}}{L_{x12}} = \frac{\omega_0}{Q} \right]$

$\frac{i_o}{N_1}(s) = \frac{1}{R_{x12}} \frac{s(\frac{\omega_0}{Q})}{s^2 + s(\frac{\omega_0}{Q}) + \omega_0^2} = \frac{1}{R_{x12}} H(s)$

Gain term

Freq. Shaping Term

Resonance magnitude



Just solve the ckt. @ resonance
 then multiply by $H(s)$!

• Go through Module 15 on Gyros, slides 1-16

