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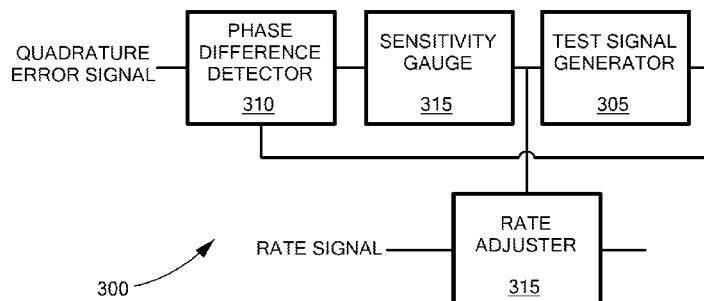


FIG. 3

(57) **Abstract:** A method compensates for a sensitivity of an inertial sensor having a resonator and an accelerometer. The method includes adding a test signal to a quadrature tuning voltage applied to the resonator of the inertial sensor. The method also includes receiving a quadrature error signal from the accelerometer of the inertial sensor. The method also includes detecting a phase difference between the quadrature error signal and the test signal. The method also includes determining a bandwidth of the accelerometer based on the detected phase difference, the bandwidth indicating the sensitivity of the accelerometer.



GYROSCOPE THAT COMPENSATES FOR FLUCTUATIONS IN SENSITIVITY

Related Application

[0001] The present application claims priority to U.S. Application No. 14/664,034, entitled “Gyroscope that Compensates for Fluctuations in Sensitivity” and filed on March 20, 2015, which is hereby incorporated by reference in its entirety.

Technical Field

[0002] The present invention relates to adjusting the rate signal of a gyroscope to compensate for the device’s sensitivity, and more particularly, to adjusting the frequency of a test signal to determine the sensitivity of the gyroscope.

Background Art

[0003] Micromachined (MEMS) gyroscopes have become established as useful commercial items. Gyroscope performance is very sensitive to such things as manufacturing variations, errors in packaging, driving, linear acceleration, and temperature, among other things. Basic principles of operation of angular-rate sensing gyroscopes are well understood and described in the prior art (e.g., Geen, J. et al., New iMEMS Angular-Rate-Sensing Gyroscope, Analog Devices, Inc., Analog Dialog 37-03 (2003), available at

<http://www.analog.com/library/analogDialogue/archives/37-03/gyro.html>, which is hereby incorporated herein by reference in its entirety).

[0004] The principles of vibratory sensing angular rate gyroscopes with discrete masses are long-established (see, for example, Lyman, US Pat. 2309853 and Lyman, US Pat. 2513340, each of which is hereby incorporated herein by reference in its entirety). Generally speaking, a vibratory rate gyroscope works by oscillating a proof mass (also referred to herein as a “shuttle” or “resonator”). The oscillation is generated with a periodic force applied to a spring-mass-damper system at the resonant frequency. Operating at resonance allows the oscillation amplitude to be large relative to the force applied. When the gyroscope is rotated, Coriolis acceleration is generated on the oscillating proof mass in a direction orthogonal to both the driven oscillation and the rotation. The magnitude of Coriolis acceleration is proportional to both the velocity of the oscillating proof mass and the rotation rate. The resulting Coriolis acceleration can be measured by sensing the deflections of the proof mass. The electrical and mechanical structures used to sense such deflections of the proof mass are referred to generally as the accelerometer.

[0005] Many MEMS gyroscopes employ balanced comb drives of the type described generally in Tang, US Pat. 5025346, which is hereby incorporated herein by reference in its entirety. General use of a micromachined layer above a semiconductor substrate with Coriolis sensing perpendicular to that substrate is described generally in Zabler, US Pat. 5275047, which is hereby incorporated herein by reference in its entirety. Exemplary MEMS gyroscopes are described in Bernstein, US Pat. 5349855; Dunn, US Pat. 5359893; Geen, US Pat. 5635640; Geen, US Pat. 5869760; Zerbini, US Pat. 6370954; and Geen US

Pat. 6837107, each of which is hereby incorporated herein by reference in its entirety. The latter four patents employ rotationally vibrated mass(es).

[0006] One problem in the manufacture of MEMS gyroscopes is that the Coriolis signals on which they depend are relatively small. It has been long recognized (e.g. Ljung, US Pat. 4884446 or O'Brien, US Pat. 5392650 or Clark, US Pat. 5992233, each of which is hereby incorporated herein by reference in its entirety) that the signal size of a vibratory gyroscope can be magnified by operating the Coriolis accelerometer at resonance, i.e., by matching the frequencies of the accelerometer to that of the vibrating shuttle. Generally speaking, this increase in signal size eases the associated electronics requirements and thereby reduces cost. However, generally speaking, the larger the resonant amplification, the more sensitive is the accelerometer phase shift to small frequency perturbations. Such phase shifts are particularly deleterious to gyroscope performance, so it is generally necessary, in practice, to either well separate the frequencies or tightly servo the frequency of the accelerometer to the frequency of the shuttle. A mechanism for controlling the frequency of a differential capacitance accelerometer is conveniently available from changing the applied common mode voltage.

[0007] One technique for sensing the frequency match in order to close a servo loop around that mechanism is to apply a small, periodic perturbation to the mechanism and servo to zero response modulated at that periodicity. This is analogous to the mode matching servo commonly used in laser gyroscopes (e.g. Ljung, US Pat. 4267478 or Curley, US Pat. 4755057, each of which is hereby incorporated herein by reference in its entirety). This method uses the quadrature signal which directly couples from the shuttle and which can be separated from the useful, in-phase signal by synchronous demodulation. In practice, the

magnitude of that signal generally varies widely and therefore is generally also subject to some control mechanism if the mode-matching servo is to have defined gain. This would be straightforward were it not that a real system generally has some other phase errors so that, for best gyro performance, the magnitude of quadrature signal should be near zero.

[0008] Another, method would be to apply a shuttle-frequency signal electromechanically to the accelerometer and synchronously demodulate the displacement output, servoing for the null which occurs at the 90 degree resonant phase shift. This inevitably interferes with the Coriolis signal and effectively is only applicable to those gyroscopes that do not need static response, such as camera stabilizing gyros.

[0009] The problem is addressed, at the expense of complexity, in Thomae, US Pat. 6654424, which is hereby incorporated herein by reference in its entirety, by applying two such signals symmetrically disposed about the desired resonance and servoing for equality of response from them. This involves two signal generators, two demodulators, two filters and a differencing means, over twice the circuitry which one might otherwise expect for the servo.

[0010] In vibratory rate gyroscopes, numerous factors, such as imperfections in the various mechanical structures and in the electronics used for driving and sensing, can cause oscillations of the accelerometer that can be confused with Coriolis acceleration and rotation rate. Such error sources are often referred to collectively as gyroscope offset. There are two main classes of gyroscope offset, namely in-phase error and quadrature error. Generally speaking, quadrature error results when the vibratory motion is not perfectly orthogonal to the accelerometer. In the presence of quadrature error, the accelerometer experiences deflections proportional to the driven displacement. In-phase error results when the vibratory drive force is not perfectly orthogonal to the accelerometer. With in-phase error,

the accelerometer experiences deflections proportional to the oscillation driving force which, at resonance, is also proportional to the oscillation velocity. Gyroscope offset can vary over time, for example, due to changes in temperature.

[0011] One possible approach to reducing gyroscope offset is to attempt to minimize the offset through device design, manufacture, and packaging, but there are practical limits to this approach.

[0012] Thus, the rate signal output by a gyroscope depends on the gyroscope's sensitivity. Because the sensitivity can fluctuate due to ambient temperature, the gyroscope may introduce different amounts of error into the rate signal depending on its environment. In this manner, for the same amount of rotation, the gyroscope would output different rate signals at different temperatures.

Summary of the Embodiments

[0013] In one aspect of the invention, a method compensates for a sensitivity of an inertial sensor having a resonator and an accelerometer. The method includes adding a test signal to a quadrature tuning voltage applied to the resonator of the inertial sensor. The method also includes receiving a quadrature error signal from the accelerometer of the inertial sensor. The method also includes detecting a phase difference between the quadrature error signal and the test signal. The method also includes determining a bandwidth of the accelerometer based on the detected phase difference, the bandwidth indicating the sensitivity of the accelerometer.

[0014] The method may also include removing errors from an output rate signal of the accelerometer according to the determined bandwidth of the accelerometer. These errors may be caused by fluctuations in sensitivity of the accelerator.

[0015] In these embodiments, the method may determining the bandwidth of the accelerometer by determining a time constant τ of the accelerometer based on the detected phase difference. Moreover, the output rate signal may be represented by $xAg\tau\Omega$. Furthermore, the method may include removing errors from an output rate signal of the accelerometer according to the determined bandwidth of the accelerometer. The errors may be removed by multiplying the output rate signal by the inverse of the determined time constant.

[0016] In some embodiments, the method also includes adjusting a frequency of the test signal until the phase difference is about equal to a predetermined value. For example, the frequency may be adjusted until the phase difference is about equal to 45 degrees. Additionally, in these embodiments, the phase difference between the quadrature error signal and the test signal may be determined by demodulating the quadrature error signal with the test signal, and determining a direct current (DC) component of the demodulated quadrature error signal. Furthermore, the frequency of the test signal may be adjusted until the direct current (DC) component of the demodulated quadrature error signal is about zero (0).

[0017] In some embodiments, detecting the phase difference between the quadrature error signal and the test signal may include demodulating the quadrature error signal with the test signal. Determining the bandwidth of the accelerometer may include determining an alternative current (AC) component of the demodulated quadrature error signal.

[0018] In another aspect of the invention, an inertial sensor that compensates for its own sensitivity includes a resonator, an accelerometer, a sensitivity circuit, and a compensating circuit. The sensitivity circuit includes a phase difference detector that detects a phase difference between a quadrature error signal from the accelerometer and a test signal. The sensitivity circuit also includes a test signal generator that generates the test signal, receives the phase difference from the phase difference detector, and adjusts a frequency of the test signal based on the phase difference. The sensitivity circuit also includes a sensitivity gauge that generates a sensitivity signal, indicative of the bandwidth of the accelerometer, based on the phase difference. The compensating circuit adjusts an output rate signal from the accelerometer based on the sensitivity signal from the sensitivity gauge.

[0019] The phase difference detector may demodulate the quadrature error signal with the test signal. The test signal generator may adjust the frequency of the test signal until the quadrature error signal and the test signal are about 45 degrees out of phase. The test signal generator may adjust the frequency of the test signal until the direct current (DC) component of the phase difference is about zero (0). The sensitivity gauge may generate the sensitivity signal based on the alternating current (AC) component of the phase difference. The compensating circuit may multiply the output rate signal by the sensitivity signal.

Brief Description of the Drawings

[0020] The foregoing features of embodiments will be more readily understood by reference to the following detailed description, taken with reference to the accompanying drawings, in which:

[0021] FIG. 1 depicts an exemplary signal from the Coriolis sense channel of an accelerometer in a gyroscope, wherein the signal includes information about the bandwidth of the channel, and thus, the time constant τ of the gyroscope;

[0022] FIG. 2 depicts an exemplary dither signal whose frequency matches the bandwidth of the Coriolis sense channel;

[0023] FIG. 3 depicts an exemplary system for compensating for the sensitivity of the gyroscope in the output rate signal;

[0024] FIG. 4 is a schematic block diagram of a system for producing the quadrature control signal used in determining the sensitivity of the gyroscope and the output rate signal;

[0025] FIG. 5 is a schematic block diagram of a system for producing the quadrature and frequency tuning voltages, to be used in conjunction with the systems described in FIGS. 2-4; and

[0026] FIGS 6 and 7 depict an exemplary gyroscope that may incorporate the systems of FIGS. 1-5.

Detailed Description of Specific Embodiments

[0027] For mode-matched gyroscopes, the sensitivity of a gyroscope introduces error into the output rate signal. Because the sensitivity fluctuates with temperature, the error in the rate signal also varies. The present solution measures the error without disturbing the normal operation of the gyroscope and removes the impact of the error from the output rate signal, thereby enabling a more accurate output to be obtained from the gyroscope.

[0028] The sensitivity of the gyroscope is manifested, at least in part, by the time constant τ of the accelerometer. The time constant τ is related to the rate at which the

accelerometer dissipates energy (e.g., the rate of decay of the accelerometer's amplitude), which can change with ambient temperature. Additionally, the rate signal output by the accelerometer of the gyroscope is proportional to the time constant τ . Assuming the gyroscope has been mode-matched (for example, by dithering the quadrature tuning voltage at a fixed dither frequency and effectively adjusting the spring constant of the accelerometer to match the accelerometer resonance frequency with the gyroscope resonator frequency as described in U.S. Patent No. 8,151,641, entitled "Mode-Matching Apparatus and Method for Micromachined Inertial Sensors", filed May 21, 2009, and hereby incorporated by reference in its entirety), the rate signal may be represented by:

$$\text{[0029]} \quad x A_g \tau \Omega$$

[0030] where Ω represents the rate of rotation;

[0031] x represents the velocity of the gyroscope's motion; and

[0032] A_g represents the gain of the gyroscope.

[0033] Therefore, measuring the time constant τ to remove its impact from the output rate signal will better enable the rate of rotation Ω to be accurately assessed.

[0034] Furthermore, the time constant τ has an inverse relationship with the bandwidth BW of the Coriolis sense channel of the accelerometer, namely, the bandwidth BW is proportional to $1/\tau$. Because signals from the Coriolis sense channel include information about the channel's bandwidth BW, and in turn, the time constant τ , these signals are processed to measure the time constant τ . An exemplary Coriolis sense channel signal carrying information about the channel's bandwidth BW, and thus the time constant τ , is depicted in FIG. 1.

[0035] The present solution compares a signal from the Coriolis sense channel (namely, the quadrature error signal) with a test signal used to dither the quadrature tuning voltage, and the phase difference indicates the relationship between the frequency of the test signal (also referred to herein as a “dither signal”) and the bandwidth of the Coriolis sense channel. When the dither frequency matches the bandwidth BW, the phase difference of the response will equal 45 degrees. An exemplary dither signal whose frequency matches the bandwidth of the Coriolis sense channel is depicted in FIG. 2. The present solution adjusts the dither frequency until the phase difference equals 45 degrees, measures the bandwidth BW (and consequently, the inverse of the time constant τ) from the response to the dither, and adjusts the output rate signal to remove the impact of the sensitivity of the gyroscope.

[0036] FIG. 3 depicts an exemplary embodiment of a system 300 that compensates for the sensitivity of the gyroscope in the output rate signal. The system 300, which is incorporated into a gyroscope, receives a quadrature error signal from the accelerometer of the inertial sensor. The quadrature error signal is based on a signal from the Coriolis sense channel and includes information about the bandwidth of the channel. The system 300 also includes a test signal generator 305 that generates a dither signal. In various embodiments, the test signal generator 305 may be a numerical control oscillator or a voltage control oscillator.

[0037] The phase difference detector 310 receives the quadrature error signal and the dither signal and determines the phase difference (also referred to herein as a “phase difference”) between the two signals. In some embodiments, the phase difference detector 310 may demodulate the quadrature error signal with the dither signal to output the phase difference. In some embodiments, the sensitivity gauge 315 passes the phase difference to

the test signal generator 305, and in other embodiments, the test signal generator 305 may receive the phase difference directly from the phase difference detector 310.

[0038] The test signal generator 305 adjusts the frequency of the dither signal until the phase difference between the quadrature error signal and the dither signal is 45 degrees. Under these conditions, the frequency of the dither signal matches the bandwidth of the Coriolis sense channel. If the frequency is higher than the bandwidth, the quadrature error signal and the dither signal would be about 90 degrees out of phase, and if the frequency is lower than the bandwidth, the two signals would be in phase.

[0039] In some embodiments, the magnitude of the direct current (DC) component of the phase difference may be proportional to the difference between the dither frequency and the bandwidth of the Coriolis signal. Thus, the DC component may indicate the phase difference between the quadrature error signal and the dither signal. For example, when the two signals are 45 degrees out of phase, demodulating the quadrature error signal with the dither signal produces a phase difference with a DC component of zero (0) or about zero. As a result, the test signal generator 305 may receive the phase difference and increase or decrease the dither frequency until it receives a signal with zero (0) DC component. In this manner, the phase difference detector 310, the sensitivity gauge 315, and the test signal generator 305 may operate collectively like a phase-locked loop.

[0040] After the test signal generator 305 drives the DC component of the phase difference to zero (0), the sensitivity gauge 315 measures the sensitivity of the gyroscope based on the phase difference. In some embodiments, the gauge 315 is a PI (e.g., proportional and integral) controller. Thus, the sensitivity gauge 315 may integrate the phase difference. In some embodiments, the sensitivity gauge 315 integrates the alternating current

(AC) component of the phase difference. In some embodiments, the gauge 315 is a counter that accumulates the phase difference. In any of these embodiments, the output of the gauge 315 is inversely proportional to the time constant τ of the gyroscope, e.g., $1/\tau$.

[0041] The sensitivity gauge 315 sends its output signal $1/\tau$ to the rate adjuster 350, which also receives the output rate signal of the gyroscope. In some embodiments, the rate adjuster 350 multiplies the sensitivity signal $1/\tau$ by the output rate signal. Because the output rate signal is represented by $x A_g \tau \Omega$, this multiplication removes the time constant τ from the rate signal, leaving $x A_g \Omega$. Because a variable error has been removed from the output rate signal, the rate of rotation may be more reliably assessed.

[0042] In this embodiment, the test signal generator 305 adjusts the frequency of the dither signal to drive the DC component of the phase difference to zero (0), and then the sensitivity gauge 315 determines the bandwidth of the accelerometer. However, in other embodiments, the test signal generator 305 may not receive feedback from the phase difference detector 310 or the sensitivity gauge 315. Instead, the test signal generator 305 merely provides a dither signal to the phase difference detector 310, and the sensitivity gauge 315 determines the bandwidth of the accelerometer from the detector's 310. For example, the sensitivity gauge 315 may use both the alternating and direct current components (AC/DC) of the detector's 310 output to determine the bandwidth.

[0043] FIG. 4 demonstrates how the quadrature error signal and output rate signal are produced in accordance with one exemplary embodiment. High frequency signals from the Coriolis sense channel are demodulated 410 with a quadrature reference signal generated by the resonator of the gyroscope to produce the quadrature error signal. This lower frequency

quadrature error signal retains information about the bandwidth of the Coriolis sense channel, and is further used to determine the sensitivity of the gyroscope.

[0044] The same Coriolis sense channel signals are also demodulated 420 with an in phase reference signal from the resonator. The resulting signal is filtered using a low pass filter 450 to produce the rate signal, which remains proportionate to the time constant τ of the gyroscope. In some embodiments, the low pass filter 450 filters out components of the signal above the dither frequency.

[0045] FIG. 5 demonstrates how the quadrature and frequency tuning voltages are produced, in accordance with one exemplary embodiment. High frequency signals from the Coriolis sense channel are demodulated 510 with a quadrature reference signal generated by the resonator of the gyroscope (e.g., the same quadrature reference signal used in the demodulation 410 to produce the quadrature control signal). This lower frequency signal is filtered via a low pass filter 510, and the result is summed via an integrator 515. The resulting signal is added 525 with a dither signal to produce the quadrature turning voltage.

[0046] The same Coriolis sense channel signals are also demodulated 530 with an in phase reference signal from the resonator (e.g., the same in phase reference signal used in the demodulation 420 used in producing the rate signal). The resulting signal is further demodulated 535 using a dither signal 535, and then summed via an integrator 540 to produce the frequency tuning voltage.

[0047] FIGS. 6 and 7 depict an exemplary gyroscope that may incorporate the systems of FIGS. 1-5. In particular, FIGS. 6 and 7 are schematic top-view diagrams of a vibratory X-Y axis gyroscope 100 in accordance with an exemplary embodiment of the present invention. This vibratory gyroscope operates generally as disclosed in Geen, U.S.

Pat. No. 5,635,640, which is hereby incorporated herein by reference in its entirety.

Specifically, this vibratory gyroscope includes various micromachined gyroscope structures in a device layer oriented above an underlying substrate having various substrate layer structures. For convenience, relevant gyroscope structures are described below with reference to axes labeled “a” and “b” in the device plane. The axes labeled “x” and “y” represent the axes about which Coriolis acceleration is sensed (i.e., the gyroscope sensing axes).

[0048] The gyroscope structures in the device plane include two rotationally-dithered masses (referred to hereinafter as shuttles) 102 and 104, each including an outer rim suspended via a number of spokes (in this case, twelve spokes, although different embodiments may use different numbers of spokes) from a central hub that is movably coupled to the substrate via a post (shaped like a “+”) and suspension flexures 101 (for convenience, only one of the two post and suspension flexure arrangements is highlighted). The posts are affixed to the substrate, and the suspension flexures allow the shuttles to oscillate rotationally, with coupling flexure 106 and support flexures 108 and 110 helping to ensure that the shuttles oscillate in anti-phase with one another (i.e., shuttle 104 rotates counterclockwise when shuttle 102 is rotating clockwise, and vice versa) nominally within the device plane. For convenience, the dithered gyroscope structures in the device plane may be referred to collectively as a resonator.

[0049] Each of the spokes includes finger structures that interdigitate with corresponding comb structures affixed to the substrate (for convenience, only two of the twenty-four sets of combs are highlighted, with each set including two combs). In this exemplary embodiment, the twenty-four sets of combs are used for driving motion of the

shuttles, where one comb in each pair is used for driving the shuttle in a clockwise direction and the other is used for driving the shuttle in a counterclockwise direction, specifically by applying alternating electrical signals to the combs to cause the shuttles 102 and 104 to oscillate through capacitive coupling with the finger structures of the spokes. Velocity sensing electrodes are used in a feedback loop to sense and control oscillation of the shuttles. In this exemplary embodiment, velocity sensing electrodes 130 on the substrate underlying the radial edges of the a-oriented and b-oriented spokes (i.e., four spokes of each shuttle) are used for velocity sensing (for convenience, only one of the eight pairs of velocity sensing electrodes is highlighted).

[0050] In this exemplary embodiment, each of the shuttles includes four protruding plates that overlie corresponding electrode arrangements on the substrate, with each electrode arrangement including a Coriolis-sensing electrode, a phase-compensating electrode, and a pair of quadrature electrodes on either side of the Coriolis-sensing and phase-compensating electrodes. Specifically, shuttle 102 includes plates 112, 114, 116, and 118 that respectively overlie arrangements (112C, 112P, 112Q), (114C, 114P, 114Q), (116C, 116P, 116Q), and (118C, 118P, 118Q), while shuttle 104 includes plates 120, 122, 124, and 126 that respectively overlie arrangements (120C, 120P, 120Q), (122C, 122P, 122Q), (124C, 124P, 124Q), and (126C, 126P, 126Q), where “C” designates the Coriolis-sensing electrode, “P” designates the phase-compensating electrode, and “Q” designates the quadrature electrodes. Each plate completely overlies the Coriolis-sensing and phase-compensating electrodes but only partially overlies the quadrature electrodes, such that capacitive coupling between the plate and each of the quadrature electrodes is dependent on the rotational position of the shuttle while capacitive coupling between the plate and the Coriolis-sensing and phase-

compensating electrodes is substantially independent of the rotational position of the shuttle. In this exemplary embodiment, the plates are positioned so as to align with the x and y axes (i.e., at approximately 45 degree angles relative to the a and b axes). It should be noted that, in this exemplary embodiment, the Coriolis-sensing electrodes are not aligned with any of the drive combs 128. The various electrodes are discussed in more detail below.

[0051] While the shuttles are oscillating at their resonance frequency (f_0), driven via the drive combs 128 with feedback provided via the velocity sensing electrodes 130, out-of-plane movements of the gyroscope about the x and y axes cause the shuttles 102 and 104 to tip out-of-plane relative to the substrate through Coriolis forces, and these out-of-plane (i.e., Coriolis axis) movements of the shuttles are detected via the Coriolis-sensing electrodes through capacitive coupling with the plates. In this exemplary embodiment, such Coriolis forces are sensed in two axes by differential capacitance with respect to the Coriolis-sensing electrodes. For example, a rotation of the gyroscope about the x-axis can cause plates 114 and 124 to move toward their respective Coriolis-sensing electrodes while plates 118 and 120 move away from their respective Coriolis-sensing electrodes, and these movements are detected by changes in capacitance between each plate and its corresponding Coriolis-sensing electrode, with the signals obtained from the four Coriolis-sensing electrodes combined to provide a gyroscope output signal representing the movement of the gyroscope. Similarly, a rotation of the gyroscope about the y-axis can cause plates 116 and 126 to move toward their respective Coriolis-sensing electrodes while plates 112 and 122 move away from their respective Coriolis-sensing electrodes. It should be noted that the plates 112, 114, 116, 118, 120, 122, 124, and 126 fully overlay their respective Coriolis-sensing electrodes throughout the entire rotational range of motion of the shuttles so that signals obtained from

the Coriolis-sensing electrodes are substantially independent of the rotational displacement of the shuttles.

[0052] Thus, the gyroscope resonator can be characterized by two modes, namely a shuttle resonance mode (i.e., the mode of the shuttles in the device plane) and an accelerometer resonance mode (i.e., the mode of the shuttles in the Coriolis axis). It is generally desirable for the two modes to match, as this tends to increase signal-to-noise ratio of the gyroscope. In embodiments of the present invention, the accelerometer resonance mode frequency is generally higher than the shuttle resonance mode frequency and the two modes are matched by effectively decreasing the accelerometer resonance mode frequency until it matches the shuttle resonance mode frequency, as discussed below.

[0053] Furthermore, even in the absence of any external movement of the gyroscope, oscillation of the shuttles typically results in slight out-of-plane movements of the shuttles, for example, due to imbalances in the shuttles and their respective support structures, and such out-of-plane movements of the shuttles can be misinterpreted as Coriolis signals and therefore represent error signals. As discussed above, such error signals may include an in-phase component and a quadrature component. While the quadrature error signals can be substantially greater than the phase error signals and therefore can swamp electronic circuitry that compensates for phase errors, it is generally desirable to remove both error components. In a gyroscope of the type shown in FIGS. 1 and 2, where the accelerometer resonance mode is out-of-plane with the shuttle resonance mode, it is generally impractical to use mechanical structures (e.g., levers and flexures) to eliminate the quadrature and in-phase error components.

[0054] Therefore, in a manner similar to that described by Clark in U.S. Pat. No. 5,992,233 or Geen in U.S. Pat. No. 7,032,451, each of which is hereby incorporated herein by reference in its entirety, quadrature adjustments are made by exerting a net torque on the shuttles in the Coriolis axis (i.e., out of the device plane). Quadrature suppression is also discussed in Lemkin, U.S. Pat. No. 7,051,590; in Chaumet, U.S. Patent Application Publication No. 2008/0282833; and in Saukoski, M., System and Circuit Design for a Capacitive MEMS Gyroscope, Doctoral Dissertation, TKK Dissertations 116, Helsinki University of Technology, Espoo, Finland (2008), each of which is hereby incorporated herein by reference in its entirety.

[0055] In the exemplary embodiment shown in FIGS. 6 and 7, quadrature adjusting electrodes on the substrate positioned under the edges of the plates (i.e., quadrature adjusting electrodes 112Q, 114Q, 116Q, 118Q, 120Q, 122Q, 124Q, and 126Q) as well as under the radial edges of the eight spokes of each shuttle positioned between the a-oriented and b-oriented spokes (i.e., quadrature adjusting electrodes 132; for convenience, only four of the sixteen pairs of quadrature adjusting electrodes 132 are highlighted) are used for making quadrature adjustments, although in alternative embodiments, similar quadrature adjustments can be made by applying bias voltages to the Coriolis sensing electrodes. A DC quadrature adjustment signal is applied to the quadrature adjusting electrodes so as to exert a net torque on the shuttles. Since the quadrature adjusting electrodes extend beyond the edges of the plates and spokes, the torque produced by the quadrature adjusting electrodes is proportional to the vibratory displacement of the shuttles in the device plane and is a function of the difference between the potentials of the electrodes. Thus, the torque causes a quadrature

motion in the Coriolis axis (i.e., the axis normal to the device plane) that is modulated by the potential of the quadrature adjusting electrodes.

[0056] It should be noted that some of the combs may be used for velocity sensing in addition to, or in lieu of, separate velocity sensing electrodes. It also should be noted that the velocity sensing electrodes 130 and the quadrature adjusting electrodes are somewhat interchangeable; a particular pair of electrodes may be used for velocity sensing and/or quadrature adjustment as desired for a particular implementation.

[0057] In practice, it can be difficult to match the accelerometer resonance mode with the shuttle resonance mode, in part because the rotational frequency of the shuttles generally changes over time, for example, due to temperature changes and other factors. Therefore, in embodiments of the present invention, a high-frequency test (carrier) signal is applied to the quadrature adjusting electrodes to induce accelerometer signals in the Coriolis channel that are 90 degrees phase shifted with respect to the Coriolis acceleration signal (i.e., the quadrature adjusting electrodes generate a quadrature output modulated by the input test signal), and the accelerometer resonance mode is adjusted by placing an appropriate biasing voltage on the gyroscope structures until there are no Coriolis channel signals at the test signal frequency. Thus, the test signal applied to the quadrature adjusting electrodes causes the quadrature motion of the shuttles to be amplitude modulated with the test frequency in the Coriolis axis. The test signal is provided at a frequency sufficiently above the gyroscope response frequency, so that the test signal is not detected by the signal filtering in the Coriolis channel and therefore does not affect the gyroscope output, but at a frequency sufficiently below the accelerometer resonance mode frequency, so that the Coriolis accelerometer will respond to the test signals. For example, in an exemplary embodiment, the

gyroscope response frequency may be below approximately 32 Hz, and the shuttle resonance mode frequency (f_0) may be approximately 64 KHz, and the test signal frequency may be an integer fraction of the shuttle resonance mode frequency, e.g., between approximately 1 KHz to 8 KHz (i.e., $f_0/64$ to $f_0/8$). Furthermore, the test signal preferably averages to zero over time and therefore may be provided so that it alternately perturbs the shuttles in one direction for half the time and in the other direction for half the time. The test signal effectively modulates the motion of the shuttles in the Coriolis axis, so the induced accelerometer signals are a product of the test signal with the motion of the shuttles.

[0058] When the modes are exactly matched, the test signal component of the Coriolis channel signals is output as just phase and the Coriolis signal is output as quadrature. When the modes are not exactly matched, however, some of the test signal shows up in the Coriolis channel signals as quadrature (i.e., there will be an out-of-phase component that is used to produce the bias signal applied to the shuttles). In order to separate the signal components, the Coriolis signal is demodulated against quadrature and the quadrature signal is demodulated against phase, as described in greater detail below.

[0059] If necessary or desirable for a particular embodiment, the average voltage on the quadrature adjusting electrodes may be adjusted independently of the test signal, for example, by a quadrature nulling servo with bandwidth much smaller than the test signal frequency. Thus, the effective quadrature output can be as near zero as is needed for accuracy while leaving a modulated quadrature signal for use in the mode frequency matching servo. That modulated signal can be demodulated against a product of the test signal with a shuttle frequency signal to give the desired servo error term. In embodiments that employ a digital demodulator (synchronous rectifier), this product can be formed, for

example, by forming an exclusive-or of the test and shuttle signals or by successive demodulation with those individual signals. There could be a residual ripple with zero mean at a harmonic of the test-signal frequency even when the frequency servo is locked, although this should not disturb the Coriolis signal if the test signal frequency is placed beyond the pass band of the Coriolis output smoothing filter, as discussed more fully below.

[0060] The embodiments of the invention described above are intended to be merely exemplary; numerous variations and modifications will be apparent to those skilled in the art. All such variations and modifications are intended to be within the scope of the present invention as defined in any appended claims.

What is claimed is:

1. In an inertial sensor having a resonator and an accelerometer, a method of measuring sensitivity of the accelerometer, the method comprising:

adding a test signal to a quadrature tuning voltage applied to the resonator of the inertial sensor;

receiving a quadrature error signal from the accelerometer of the inertial sensor;

detecting a phase difference between the quadrature error signal and the test signal;

and

determining a bandwidth of the accelerometer based on the detected phase difference, the bandwidth indicating the sensitivity of the accelerometer.

2. The method of claim 1, further comprising:

removing errors, caused by fluctuations in sensitivity of the accelerator, from an output rate signal of the accelerometer according to the determined bandwidth of the accelerometer.

3. The method of claim 1, wherein determining the bandwidth of the accelerometer comprises:

determining a time constant τ of the accelerometer based on the detected phase difference.

4. The method of claim 3,
wherein the output rate signal is represented by $xAg\tau\Omega$, and
wherein the method further comprises removing errors, caused by fluctuations in sensitivity of the accelerator, from an output rate signal of the accelerometer according to the determined bandwidth of the accelerometer, by multiplying the output rate signal by the inverse of the determined time constant.
5. The method of claim 1, further comprising:
adjusting a frequency of the test signal until the phase difference is about equal to a predetermined value.
6. The method of claim 5, wherein adjusting the frequency of the test signal comprises:
adjusting the frequency of the test signal until the phase difference is about equal to 45 degrees.
7. The method of claim 5, wherein detecting the phase difference between the quadrature error signal and the test signal comprises:
demodulating the quadrature error signal with the test signal; and
determining a direct current (DC) component of the demodulated quadrature error signal.

8. The method of claim 7, wherein adjusting the frequency of the test signal until the phase difference is about equal to a predetermined value comprises:

adjusting the frequency of the test signal until the direct current (DC) component of the demodulated quadrature error signal is about zero (0).

9. The method of claim 1, wherein detecting the phase difference between the quadrature error signal and the test signal comprises:

demodulating the quadrature error signal with the test signal.

10. The method of claim 9, wherein determining the bandwidth of the accelerometer comprises:

determining an alternating current (AC) component of the demodulated quadrature error signal.

11. An inertial sensor that compensates for its own sensitivity, comprising:

a resonator;

an accelerometer;

a sensitivity circuit including

a phase difference detector that detects a phase difference between a quadrature error signal from the accelerometer and a test signal,

a test signal generator that (1) generates the test signal, (2) receives the phase difference from the phase difference detector, and (3) adjusts a frequency of the test signal based on the phase difference; and

a sensitivity gauge that generates a sensitivity signal, indicative of the bandwidth of the accelerometer, based on the phase difference;

a compensating circuit that adjusts an output rate signal from the accelerometer based on the sensitivity signal from the sensitivity gauge.

12. The inertial sensor of claim 11, wherein the phase difference detector demodulates the quadrature error signal with the test signal.

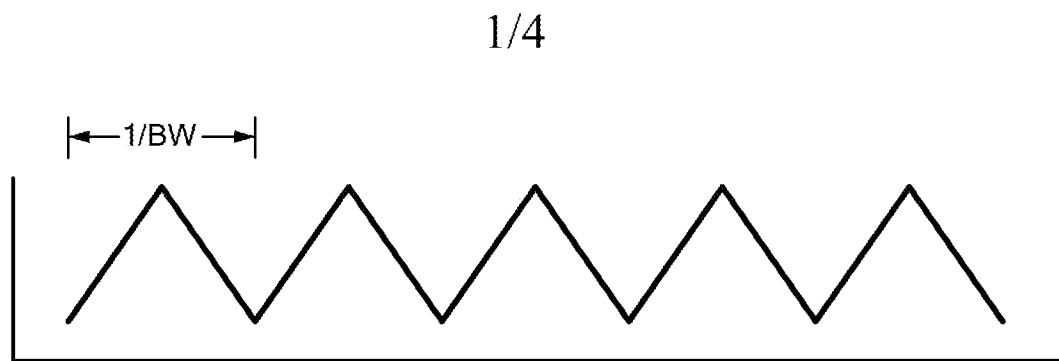
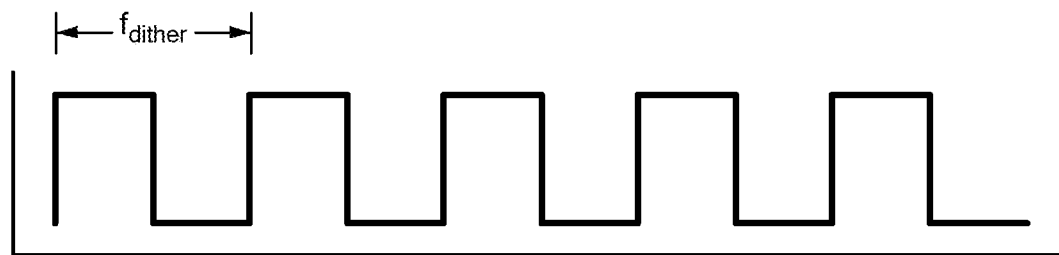
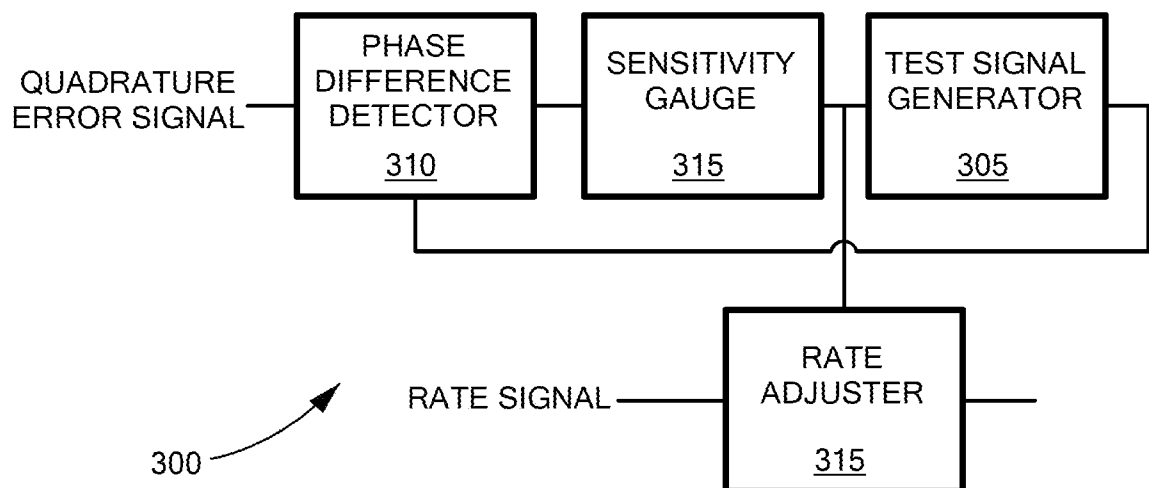
13. The inertial sensor of claim 11, wherein the test signal generator adjusts the frequency of the test signal until the quadrature error signal and the test signal are about 45 degrees out of phase.

14. The inertial sensor of claim 11, wherein the test signal generator adjusts the frequency of the test signal until the direct current (DC) component of the phase difference is about zero (0).

15. The inertial sensor of claim 11, wherein the sensitivity gauge generates the sensitivity signal based on an alternating current (AC) component of the phase difference.

16. The inertial sensor of claim 11, wherein the compensating circuit multiplies the output rate signal by the sensitivity signal.

17. An electronic circuit for an inertial sensor that compensates for its own sensitivity, the inertial sensor including a resonator and an accelerometer, the electronic circuit comprising:
- a sensitivity circuit including:
 - a phase difference detector that detects a phase difference between a quadrature error signal from the accelerometer and a test signal,
 - a test signal generator that (1) generates the test signal, (2) receives the phase difference from the phase difference detector, and (3) adjusts a frequency of the test signal based on the phase difference, and
 - a sensitivity gauge that generates a sensitivity signal, indicative of the bandwidth of the accelerometer, based on the phase difference; and
 - a compensating circuit that adjusts an output rate signal from the accelerometer based on the sensitivity signal from the sensitivity gauge.
18. The inertial sensor of claim 17, wherein the phase difference detector demodulates the quadrature error signal with the test signal.
19. The inertial sensor of claim 17, wherein the test signal generator adjusts the frequency of the test signal until the phase difference is about equal to a predetermined value.
20. The inertial sensor of claim 17, wherein the sensitivity gauge generates the sensitivity signal based on an alternating current (AC) component of the phase difference.

**FIG. 1****FIG. 2****FIG. 3**

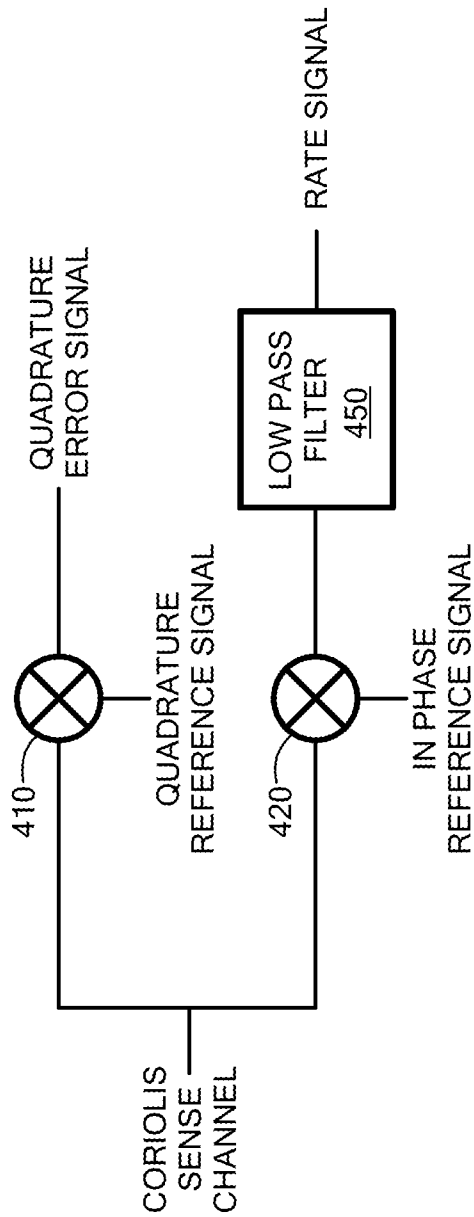


FIG. 4

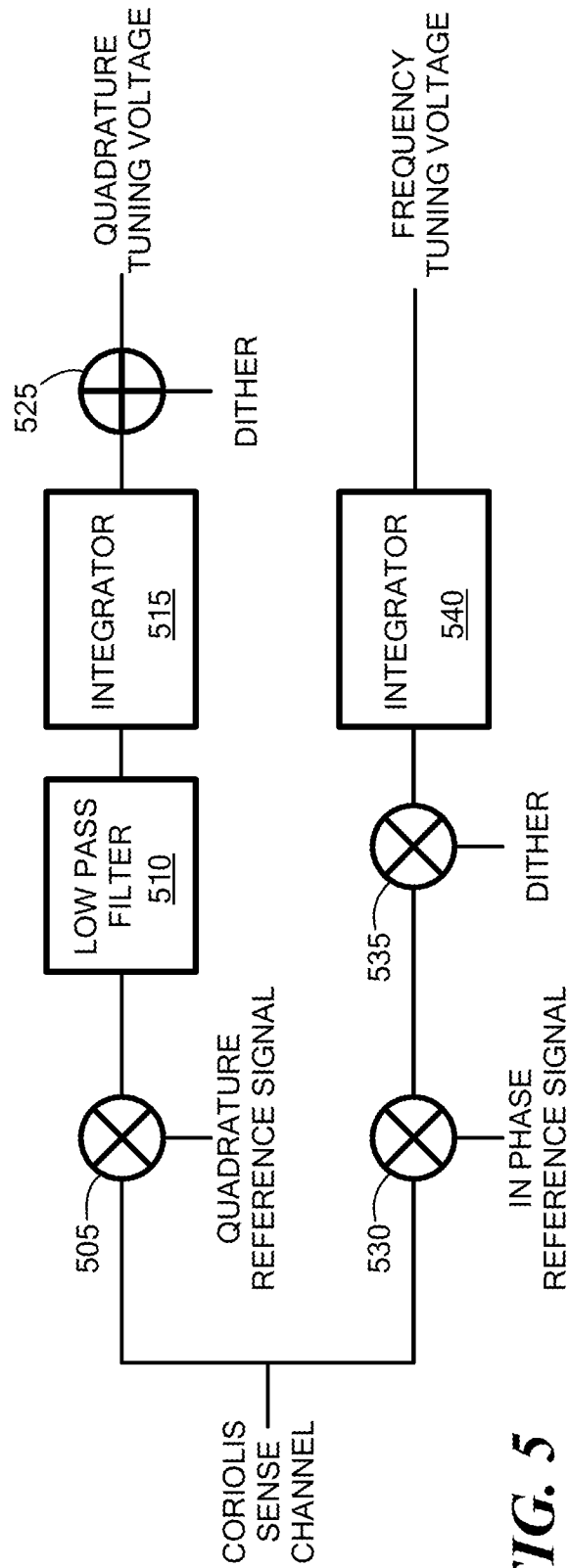


FIG. 5

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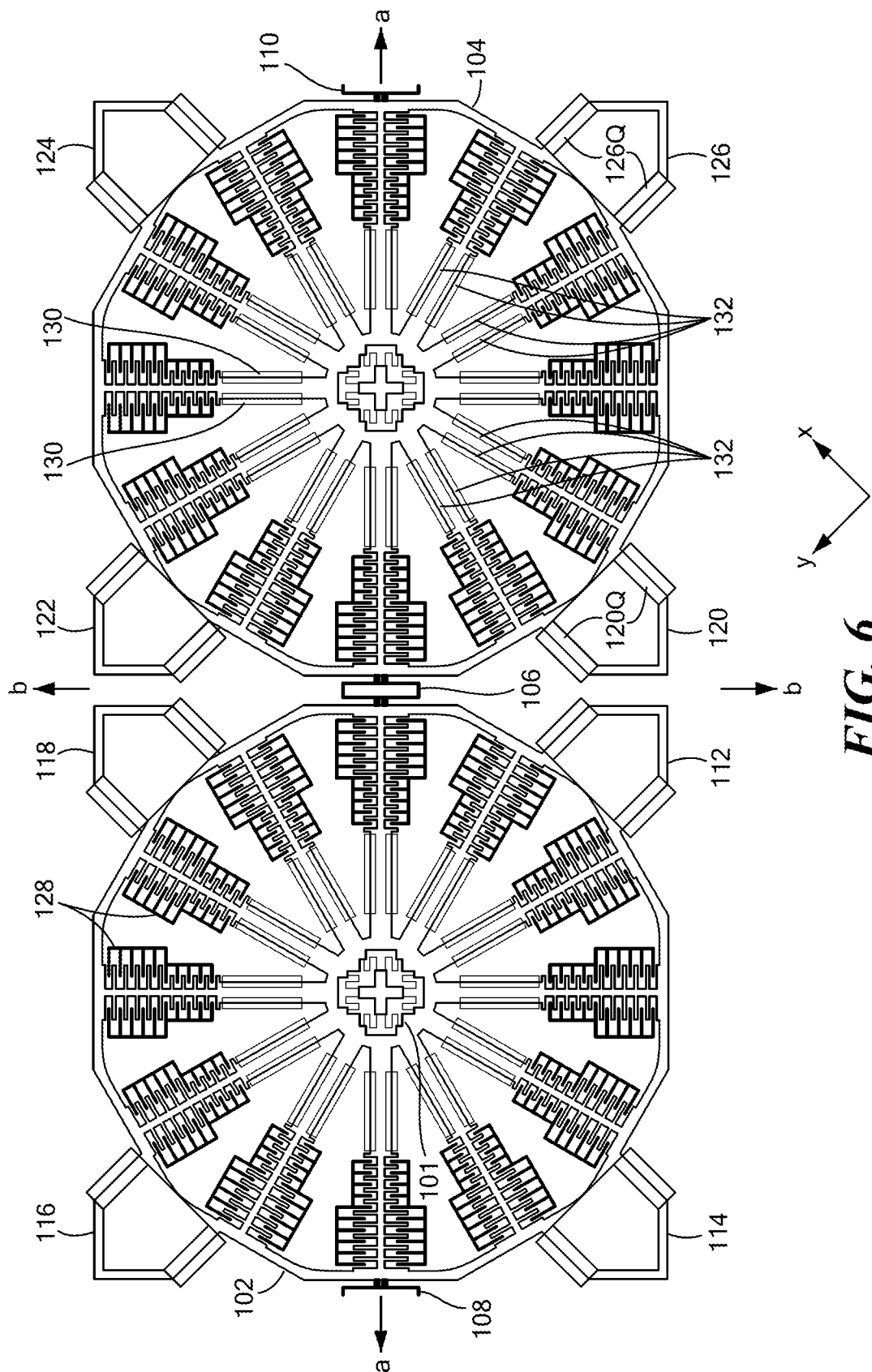


FIG. 6

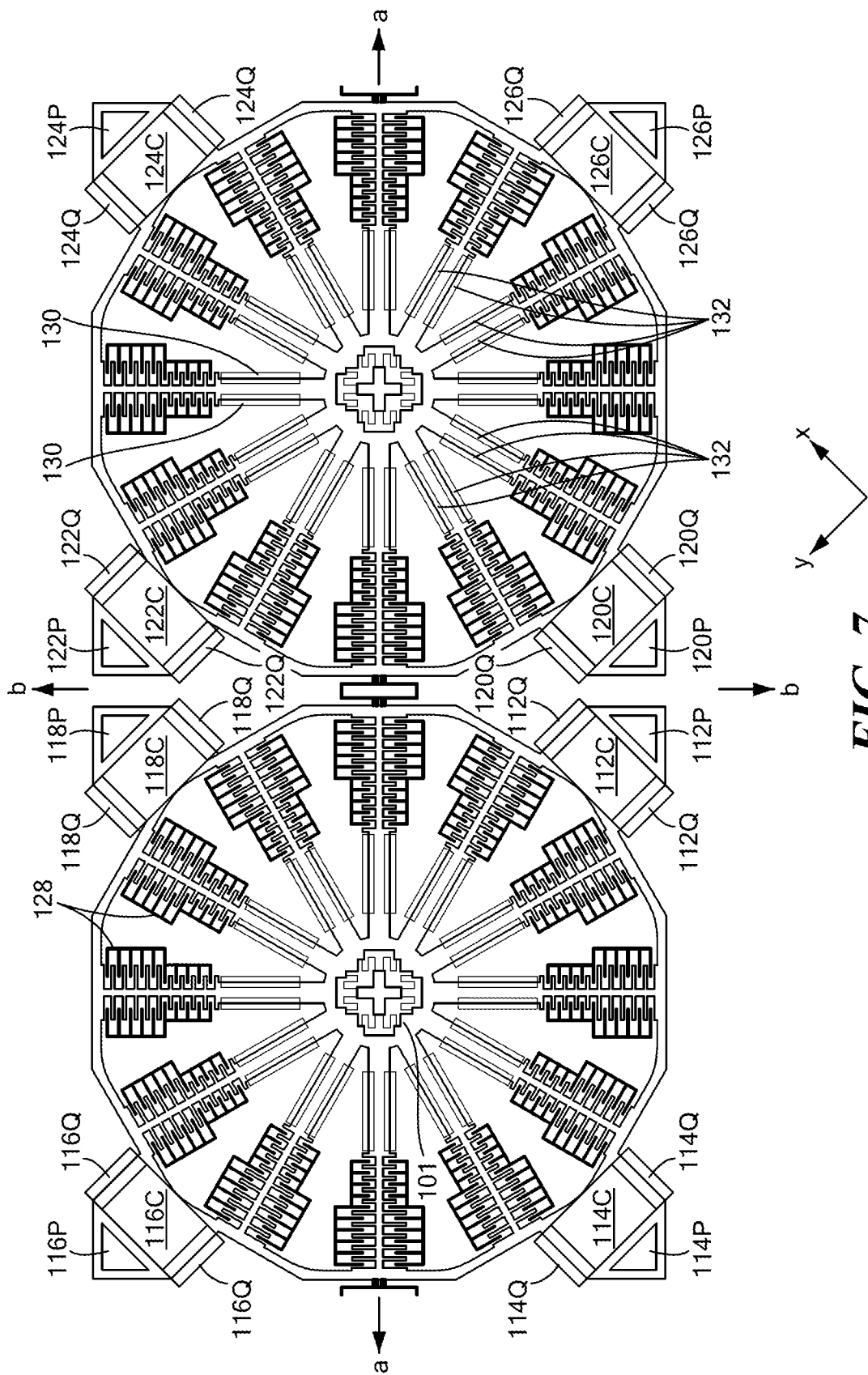


FIG. 7

INTERNATIONAL SEARCH REPORT

International application No.

PCT/US2016/018381

A. CLASSIFICATION OF SUBJECT MATTER IPC (2016.01) G01C 19/577600, G01C 19/568400, G01C 19/56 According to International Patent Classification (IPC) or to both national classification and IPC		
B. FIELDS SEARCHED Minimum documentation searched (classification system followed by classification symbols) IPC (2016.01) G01C 19/577600, G01C 19/568400, G01C 19/56 Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched Electronic data base consulted during the international search (name of data base and, where practicable, search terms used) Databases consulted: THOMSON INNOVATION, Esp@cenet, Google Patents, Google Scholar		
C. DOCUMENTS CONSIDERED TO BE RELEVANT		
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X	"An Automatically Mode-Matched MEMS Gyroscope With Wide and Tunable Bandwidth" Journal of Microelectromechanical Systems, Vol. 23, No. 2, pages 284-297. Sonmezoglu et al. 14 Apr 2014 (2014/04/14) (The whole documents especially, Figs. 1, 2, 3, 4, equation 6).	1-20
A	"Quadrature-Error Compensation and Corresponding Effects on the Performance of Fully Decoupled MEMS Gyroscopes" Journal of Microelectromechanical Systems, Volume: 21, Issue: 3, page(s): 656 – 667. Tatar et al. 01 Jun 2012 (2012/06/01) (The whole document especially abstract, Figs. 1-4, 9-12).	1-20
Y	"A Digitalized Silicon Microgyroscope Based on Embedded FPGA" Sensors 12, 13150-13166. Xia et al. 01 Jan 2012 (2012/01/01) (Fig. 3, #2.1, #2.2).	1-20
Y	Thesis "Characterization Control and Compensation of MEMS Rate and Rate-Integrating Gyroscopes" Gregory Gregory 01 Jan 2012 (2012/01/01) (#4.2.1, equations 4.3, 4.4, 4.8, 4.9).	4,16
☒ Further documents are listed in the continuation of Box C. ☒ See patent family annex.		
* Special categories of cited documents: "A" document defining the general state of the art which is not considered to be of particular relevance "E" earlier application or patent but published on or after the international filing date "L" document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified) "O" document referring to an oral disclosure, use, exhibition or other means "P" document published prior to the international filing date but later than the priority date claimed "T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention "X" document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone "Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art "&" document member of the same patent family		
Date of the actual completion of the international search 23 May 2016		Date of mailing of the international search report 01 Jun 2016
Name and mailing address of the ISA: Israel Patent Office Technology Park, Bldg.5, Malcha, Jerusalem, 9695101, Israel Facsimile No. 972-2-5651616		Authorized officer NIMER Emad Telephone No. 972-2-5657801

INTERNATIONAL SEARCH REPORT

International application No.

PCT/US2016/018381

C (Continuation). DOCUMENTS CONSIDERED TO BE RELEVANT		
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
A	"A Closed-Loop Digitally Controlled MEMS Gyroscope With Unconstrained Sigma-Delta Force-Feedback" IEEE Sensors Journal, Volume.9, Issue.3, pp.297, 2009, ISSN: 1530437X. Raman et al. 01 Mar 2009 (2009/03/01) (The whole document).	1-20
A	US 2014250970 A1 FANG et al. 11 Sep 2014 (2014/09/11) (The whole documents especially, Figs. 1-4, paragraph 28-38, note the test signal generator 124, Figs. 1-2, and the Quad control 234, Fig. 2).	1-20
A	WO 2014093727 A1 Izyumin 19 Jun 2014 (2014/06/19) (Figs. 1, 8, 10-20).	1-20
A	US 2010089158 A1 Watson. 15 Apr 2010 (2010/04/15) (The whole document).	1-20
A	US 6553833 B1 Funk et al. 29 Apr 2003 (2003/04/29) (The whole document especially abstract, Fig. 3).	1-20
A	US 2009064781 A1 Ayazi et al. 12 Mar 2009 (2009/03/12) (Figs. 3, 4, 9).	1-20

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				CN	104919275	A	16 Sep 2015
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				US	8061201	B2	22 Nov 2011
				US	2012192647	A1	02 Aug 2012
				US	8677821	B2	25 Mar 2014