

## Motivation

- The performance of MEMS gyroscopes is rapidly approaching the level that can be adopted in a wide range of military and high-end industrial applications.
- One of the most highly desired applications for a high-performance gyroscope is GPS-free inertial navigation for autonomous cars, drones, and indoor pedestrians and it is required to have very high bias stability (< 0.1 deg/hr)

## Objective

- Implementation of a front-end capacitive readout circuitry with extremely low noise, wide dynamic range, and high tolerance to variations in voltage and temperature to overcome the performance limits of existing gyroscopes.
- Implementation of a front-end capacitive readout circuitry with a wide feedback control range to detect a wide range of capacitances and frequencies

## Challenges of Front-End Circuitry

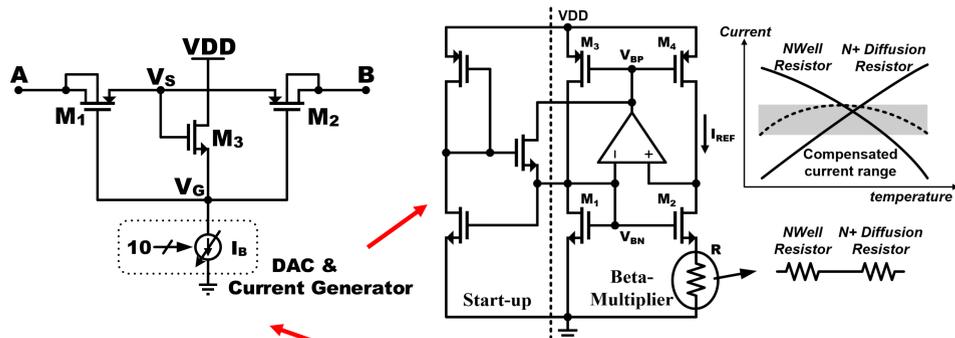
- Large output swing to cover a wide range of sensitivity
- Low distortion to get the high linearity
- Large and controllable feedback gain to cover a wide range of capacitances
- Easy on-chip integration to reduce parasitic

## Trans-impedance Amplifier for Front-End

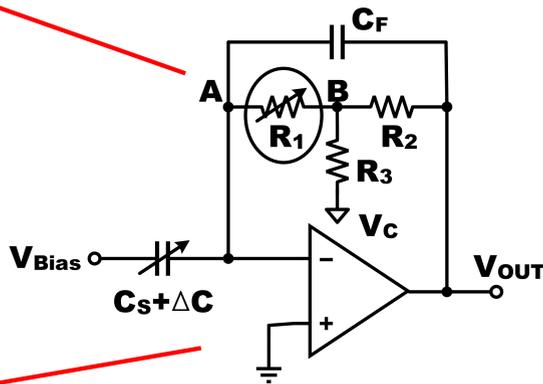
- Relatively insensitive to parasitic
- Easy control of feedback gain
- Two-chip cost effective solution
- Proof-mass not switched

## Entire Circuit Implementation

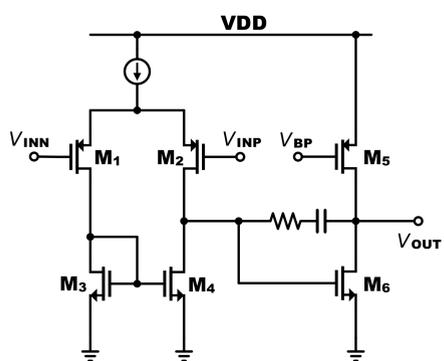
- Variable Floating Resistor with 10-b Current Steering DAC
- Voltage-Temperature tolerant Current Generator



- TIA with Floating Resistor T-Network
  - Covers wide range of readout capacitances and frequency ranges
  - Compensates for process and temperature variations
  - Reduces TIA noise by the integrated resistance control block



- Low-noise Two Stage Amplifier



$$V_{n,thermal}^2 \approx \frac{16kT}{3} \frac{1}{g_{m1}^2} (g_{m1} + g_{m3})$$

$$V_{n,flicker}^2 \approx \frac{2}{C_{ox}f} \left( \frac{K_p}{W_1 L_1} + \frac{\mu_n K_n L_1}{\mu_p W_1 L_3^2} \right)$$

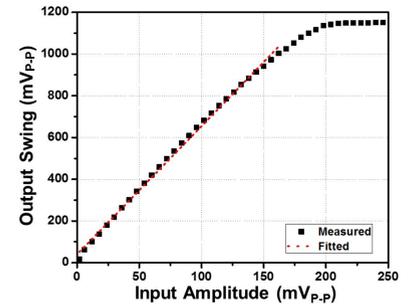
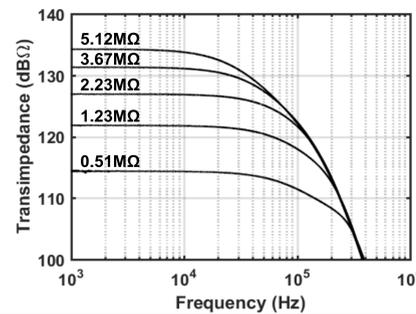
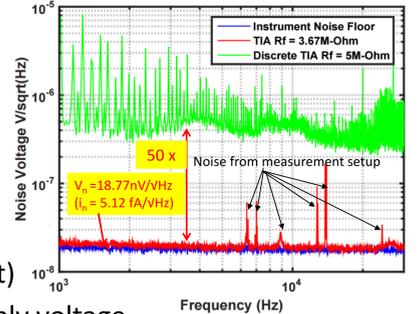
- $W_1 \uparrow$  →  $g_{m1} \uparrow$  → Thermal noise ↓
- $L_3 \uparrow$  → Sig. swing ↓
- Flicker noise ↓

## Accomplishments

- Implemented a new TIA that employs an on-chip digitally-controlled floating resistor as the variable resistor for a resistor T-network to lower the noise and obtain higher linearity .
- Measured **very low input current noise ( $i_n=5.12\text{fA}/\sqrt{\text{Hz}}$ ) which translates to **0.45 zF/VHz minimum detectable capacitance and very wide dynamic range (123 dB).****
- Demonstrated **near-navigation-grade bias instability (0.0391 deg/hr).**

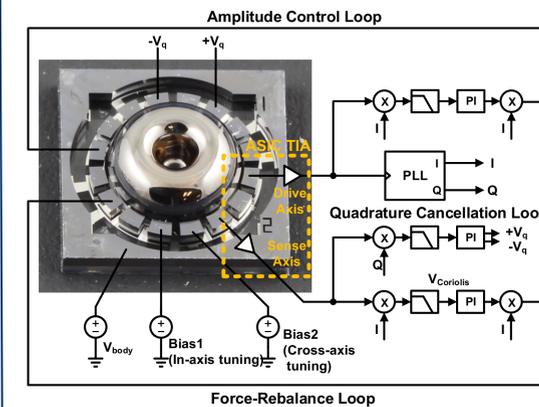
## Evaluation of Proposed CMOS TIA

- Comparison between output noise spectral densities of TIA ASIC and discrete low-noise TIA (Right)
  - ~50 times lower noise floor
- Measured T-network TIA gain (Lower Left)
  - Wide and controllable feedback gain
- Measured T-network TIA gain (Lower Right)
  - Large output swing even with low supply voltage



## Performance Summary and Comparison Results

Technology	0.18 μm 1P6M CMOS
Feedback Gain Range	510kΩ-5.12MΩ
Output swing	Up to 955mV <sub>p-p</sub>
Input referred current noise	5.12 fA/√Hz (@10KHz)
Min. detectable capacitance	0.45 zF/VHz
Dynamic Range	123dB



Resonator Dimension	Radius (R): 2.5 mm Height (H): 1.55 mm
Frequency ( $f_n=2$ )	9030.925 Hz 9030.998 Hz
Quality Factor	419.047k (14.77s) 410.176k (14.14s)
Scale Factor	100 mV/deg/s
Bias Stability	0.0391 deg/h

References	J.A. Geen et al.	A. Sharma et al.	L. Aaltonen et al.	This work
Front-End Architecture	CSA*	TIA	CSA*	TIA
Input Current Noise (fA/√Hz)	-	88	-	5.12
Minimum Detectable Cap. (zF/VHz)	12 (zF)	20**	220	0.45***
Bias instability (deg/h)	50	0.16	25	0.0391

\*: Charge sense amplifier \*\*:  $V_{Bias}=40\text{V}, f=15\text{kHz}$  \*\*\*:  $V_{Bias}=200\text{V}, f=9.03\text{kHz}$

## Summary and Future Work

- Demonstrated the fully integrated CMOS TIA with **one-of-the lowest reported noise performance and very wide dynamic range.**
- Demonstrated the rate-mode operation of FS μ-BRG with **one-of-the-best performance among existing MEMS gyroscopes.**
- Will implement a miniaturized system with low-noise and high performance.