



CENG4480

## Lecture 05: Sensors

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# Overview



## 1. Motion Sensors

- 1-1. Accelerometer
- 1-2. Gyroscope
- 1-3. Compass
- 1-4. Tilt Sensor

## 2. Force Sensors

- 2-1. Force Sensing Resistor
- 2-2. Strain Gauge
- 2-3. Flexion (bend) sensors
- 2-4. Air Pressure Sensor

## 3. Other Sensors

- 3-1. Position sensors
- 3-2. Temperature and humidity
- 3-3. Optical Sensors
- 3-4. Hall Effect Sensors
- 3-5. Kinect Sensors

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# 1-1. Accelerometer



- ▶ Electromechanical devices that sense
  - ▶ **Static** acceleration (gravity)
  - ▶ **Dynamic** acceleration (vibrations & movement)
- ▶ Functions:
  - ▶ measure acceleration in one or more directions, position can be deduced by integration.
  - ▶ Orientation sensing: tilt sensor
  - ▶ Vibration sensing
  - ▶ measure acceleration in one or more directions, position can be deduced by integration.
- ▶ Methods:
  - ▶ **Mass spring** method ADXL78 (from Analog Device)
  - ▶ **Air pocket** method (MX2125)





# ADXL78 (Mass Spring Method)

- ▶ Click this [online document](#)
- ▶ Measure the capacitance to create output
- ▶ Measure both dynamic & static acceleration

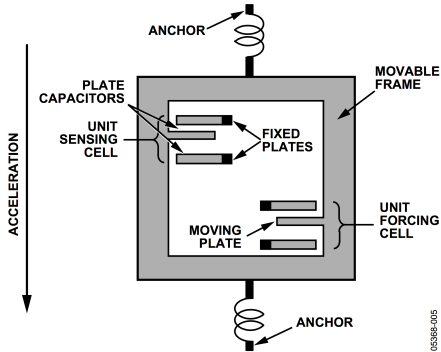


Figure 5. Simplified View of Sensor Under Acceleration

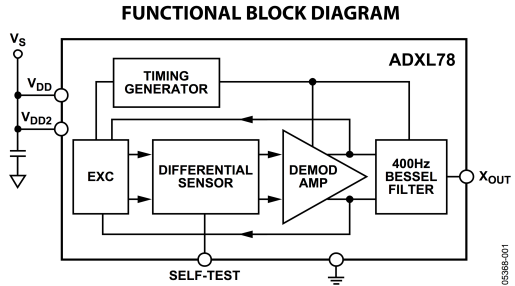
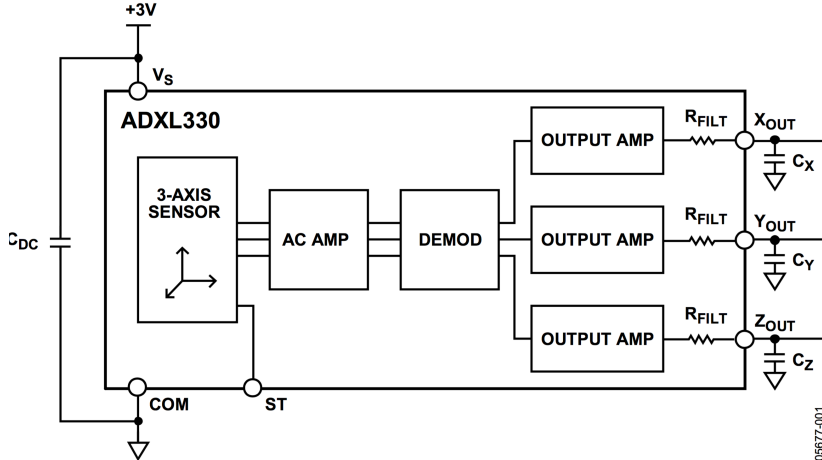


Figure 1.



# ADXL330 Accelerometer for (X, Y, Z) Directions

- ▶ [Click this online document](#)
- ▶ 3D



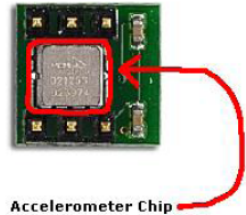
05677-001

Figure 1.

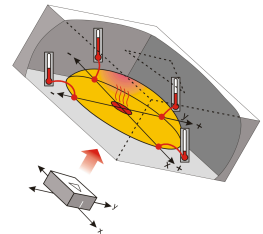
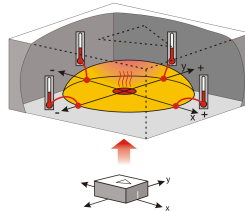
# 2D Translational Accelerometer MX2125



Accelerometer Module



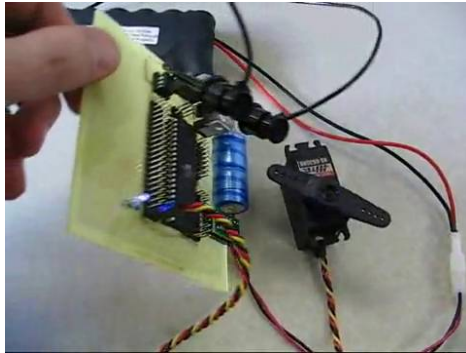
Accelerometer Chip



- ▶ Click this [online document](#)
- ▶ Gas pocket type

- ▶ When the sensor moves, the temperatures of the 4 sensors are used to evaluate the 2D accelerations

# Demo: orientation sensing

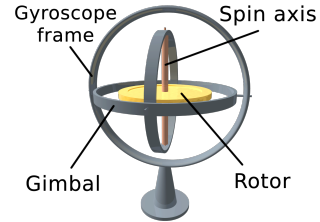


(<https://youtu.be/9NEiBDBXFEQ>)

# 1-2. Gyroscopes



- ▶ [wiki page](#)
- ▶ Measure rotational angle



## Rate Gyroscope

- ▶ Measure the rate of rotation along 3-axes of X (pitch), Y (roll), and Z (yaw).
- ▶ Modern implementations are using Microelectromechanical systems (MEMS) technologies.

# Gyroscope to Measure Rational acceleration

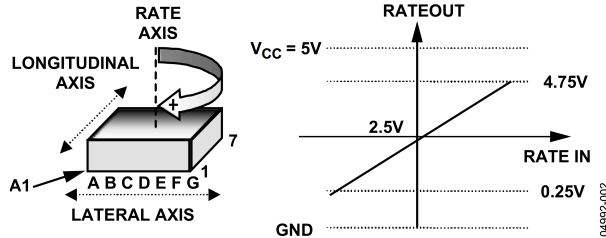


Figure 2. RATEOUT Signal Increases with Clockwise Rotation

## Features

- ▶ Complete rate gyroscope on a single chip Microelectromechanical systems (MEMS)
- ▶ Z-axis (yaw-rate) response

## Applications

- ▶ GPS navigation systems
- ▶ Image stabilization
- ▶ Inertial measurement units
- ▶ Platform stabilization

# 1-3. Compass



- ▶ Philips KMZ51 magnetic field sensor
- ▶ 50/60Hz (high) operation, a jitter of around  $1.5^\circ$

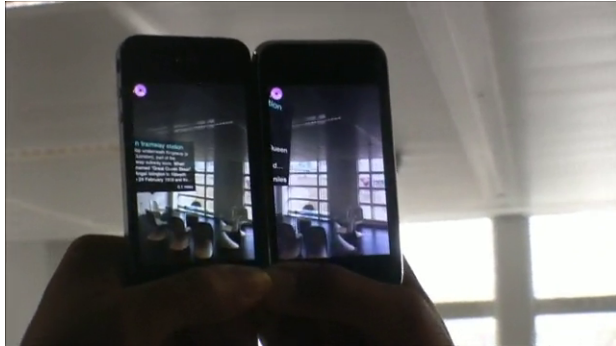


- Pin 9 - 0v Ground
- Pin 8 - No Connect
- Pin 7 - 50/60Hz
- Pin 6 - Calibrate
- Pin 5 - No Connect
- Pin 4 - PWM
- Pin 3 - SDA
- Pin 2 - SCL
- Pin 1 - +5v

# Rate gyroscope demo



Using Gyroscope compass for virtual reality application in an iphone



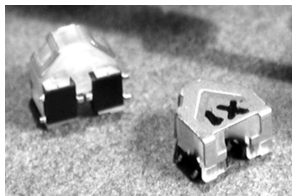
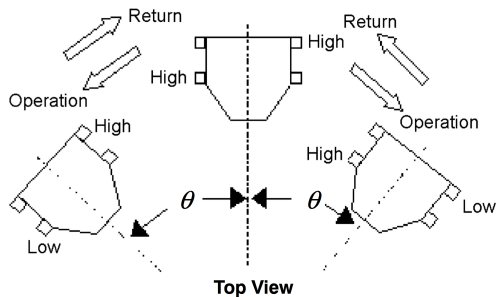
(<https://youtu.be/VP4-wdMMLFo>)





# 1-4. Tilt Sensor by OMRON

- ▶ Click this [online document](#)
- ▶ Detect tilting 35 ~ 65 degrees in right-and-left inclination



↓  
Gravity  
direction

- Note: 1. Operation angle: Output goes from High to Low  
2. Return angle: Output goes from Low to High

# Demo: Tilt Sensing



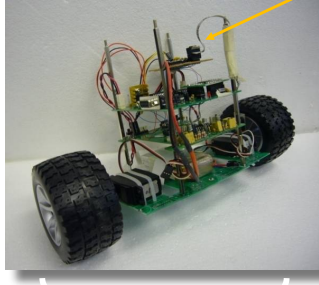
(<https://youtu.be/C6uVrYz-j70>)

One more reference: <https://youtu.be/KZVgKu6v808>.

# Application – Self Balancing Robot



20cm



Motion sensors:  
gyroscope and  
accelerometer

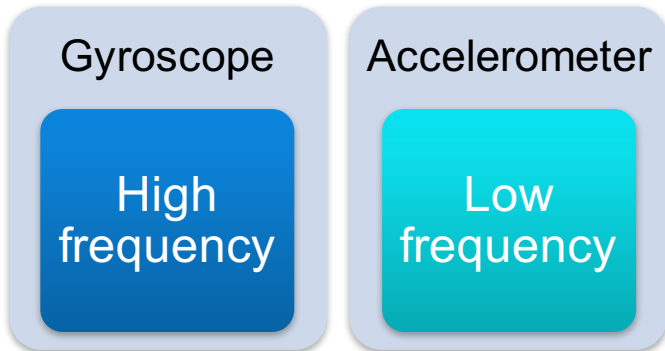
35cm

by Kelvin Ko (<https://youtu.be/2u-E02FDFG0>)

# Complementary Filter

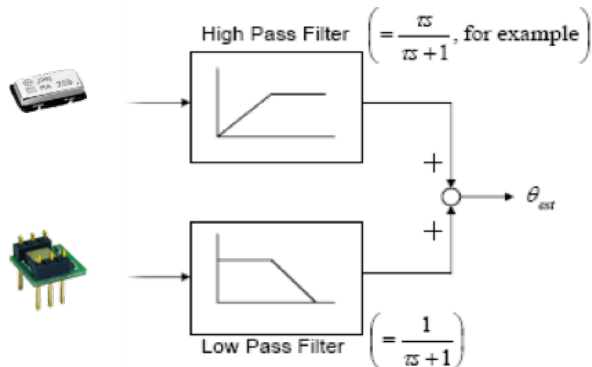


- ▶ Since



- ▶ Combine two sensors to find output

# Complementary Filter (cont.)



- ▶  $\theta$ : rotation angle
- ▶  $\tau$ : filter time constant
- ▶  $s$ : Laplace operator

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## 2-1. Force Sensing Resistors

- ▶ FSR402
- ▶ Exhibits a decrease in resistance with an increase in the force applied to the active surface.
- ▶ Click [this online document](#)

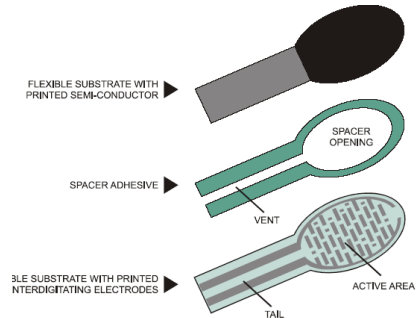
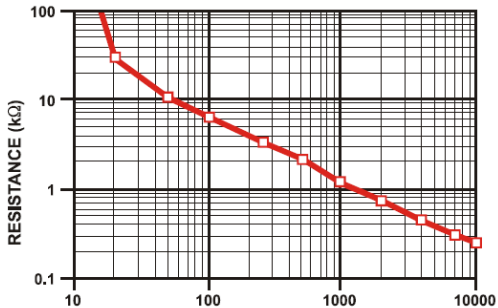
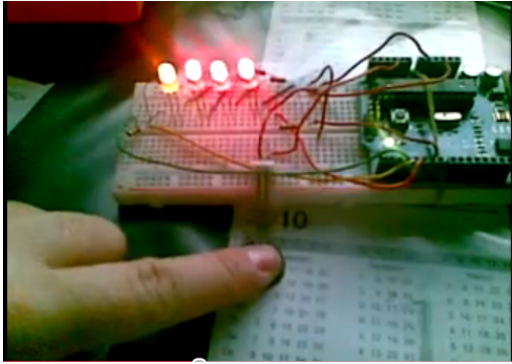


Figure 1: FSR Construction

# Force Sensing Resistor Demo



(<https://youtu.be/LQ211Xr6egs>)



# Application 1: Walking Robot



## ► Balancing

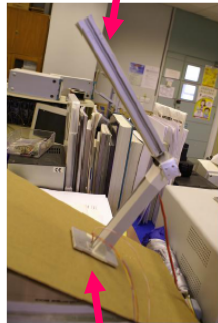
Neutral position



Floor tilted left  
upper leg bend right

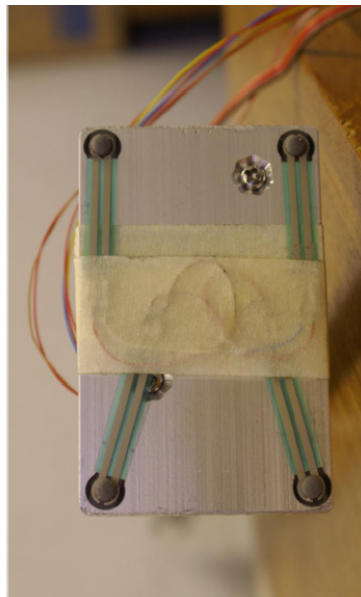
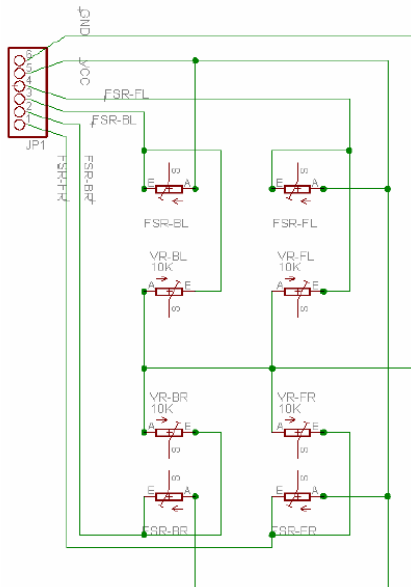


Floor tilted right  
upper leg bend left



Four sensors under the foot

# Four Force sensors under the foot



## Application 2: The Nao Robot



- ▶ uses force feedback at its feet
- ▶ [wiki page](#)



(<https://youtu.be/2STTNYNF41k>)

# Application 3: Robot Dog from Boston Dynamics



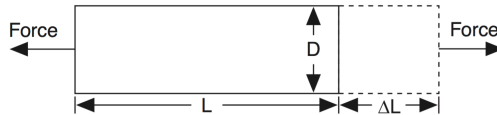
(<https://youtu.be/wXxrmussq4E>)

## 2-2. Strain Gauge



### What's Strain?

Amount of deformation of a body due to an applied force.



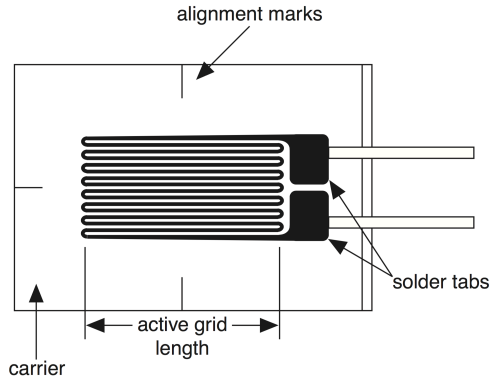
$$\varepsilon = \frac{\Delta L}{L}$$

**Figure 1.** Definition of Strain



# Strain Gauge (cont.)

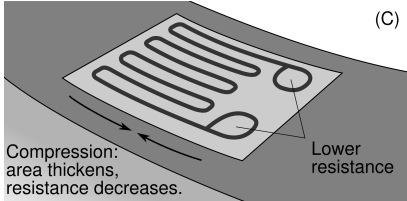
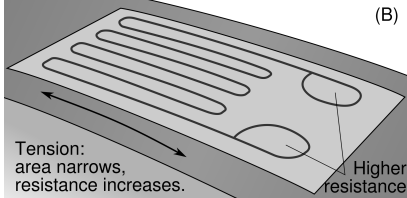
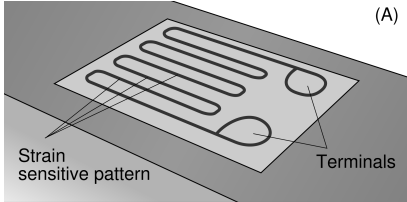
- ▶ **Piezoelectric crystal:** produces a voltage that is proportional to force applied
- ▶ **Strain gauge:** a device for indicating the strain of a material or structure at the point of attachment
- ▶ Cemented on a rod. One end of the rod is fixed, force is applied to the other end. The resistance of the gauge will change with the force.



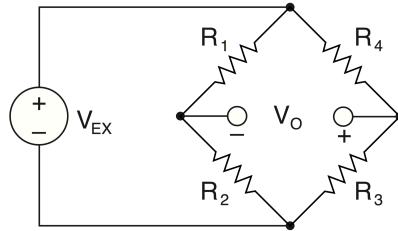
# Strain Gauge (cont.)



Ex: mechanical strain gauge used to measure the growth of a crack in a masonry foundation.



# Wheatstone Bridge



## Wheatstone Bridge

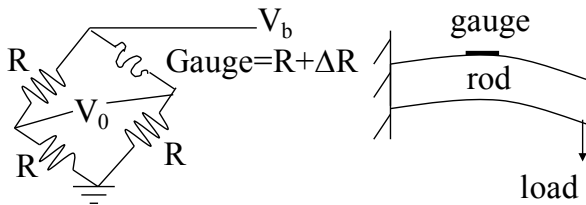
$$V_O = \left[ \frac{R_2}{R_1 + R_2} - \frac{R_3}{R_3 + R_4} \right] \cdot V_{EX}$$





# Single Element Strain Gauge

Sensitive to temperature change.



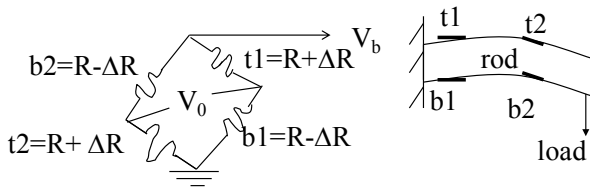
## Out Voltage

$$V_O = \left[ \frac{R}{2R} - \frac{R}{2R + \Delta R} \right] \cdot V_b = \left[ \frac{\Delta R}{4R + 2\Delta R} \right] \cdot V_b$$
$$\approx \frac{\Delta R}{4R} \cdot V_b$$

# Four-Element Strain Gauge



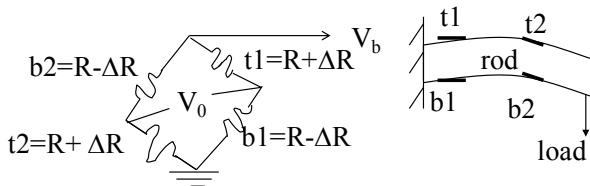
- ▶ **Four times more sensitive** than single gauge system
- ▶ **NOT sensitive** to temperature change.
- ▶ All gauges have unstrained resistance  $R$ .





## Question

For four-element strain gauge, calculate  $\frac{V_O}{V_b}$ .

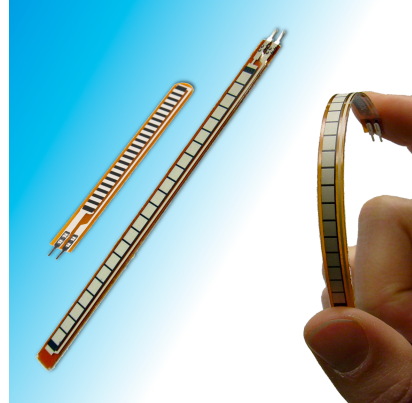


## 2-3. Flexion (bend) sensors



Resistance:

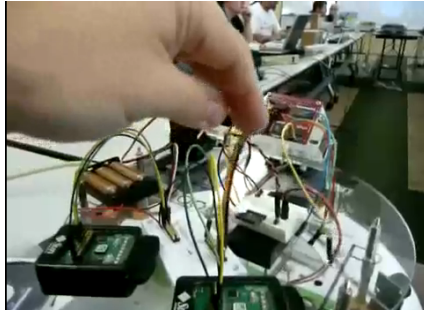
- ▶  $10\text{ K}\Omega$  ( $0^\circ$ );
- ▶  $30\text{--}40\text{ K}\Omega$  ( $90^\circ$ )



<https://youtu.be/1EUV1SsAhCg>

Click this [online document](#)

# Felixon resistance Demo

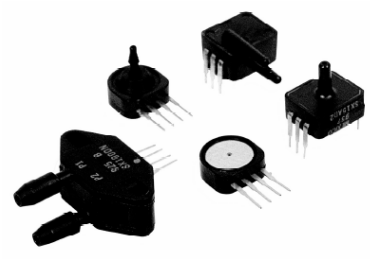


(<https://youtu.be/m4E5SP7HCnk>)

## 2-4. Air Pressure Sensor



- ▶ Measure up to 150 **psi** (pressure per square inch).



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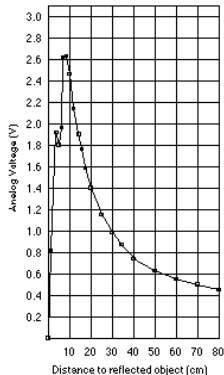
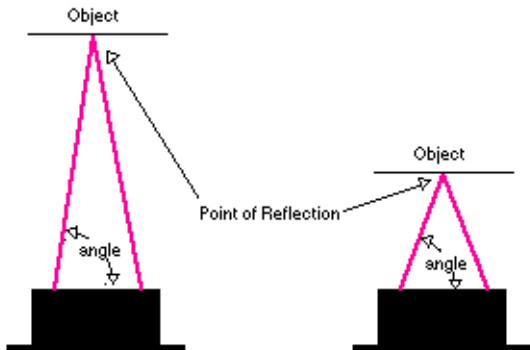
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# Infra-red Range detectors

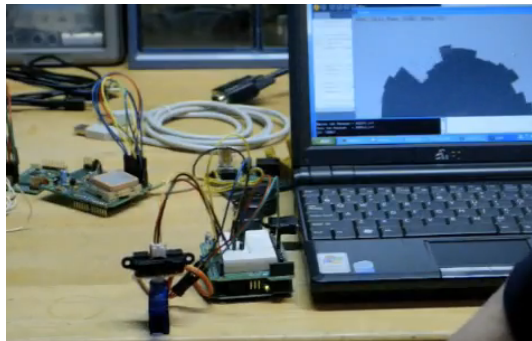
- ▶ by SHARP (4 to 30 cm)
- ▶ An emitter sends out light pulses. A small linear CCD array receives reflected light.
- ▶ The distance corresponds to the triangle formed.



<http://www.acroname.com/robotics/info/articles/sharp/sharp.html>



# IR radar using the Sharp range detector

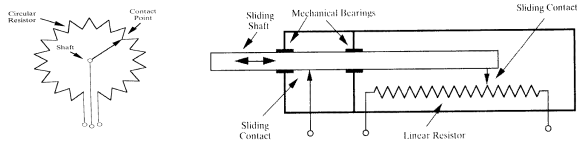


<https://youtu.be/tStBLAiQaC8>

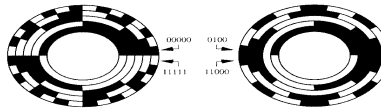
# Position Sensors



## ▶ Rotary



## ▶ Rotary Encoder

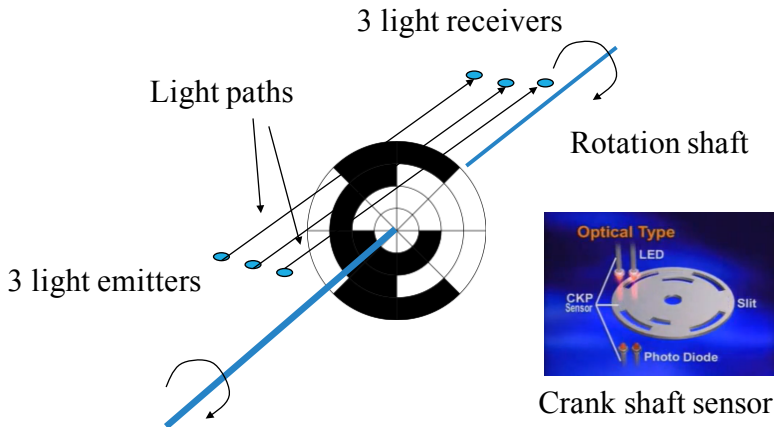


## ▶ Digital Linear Encoder

# Optical Rotary Encoder



- ▶ [wiki page](#)
- ▶ <https://youtu.be/RuIis1TG0wA>
- ▶ The light received (on or off) will tell the rotation angle



# Magnetic rotary encoder



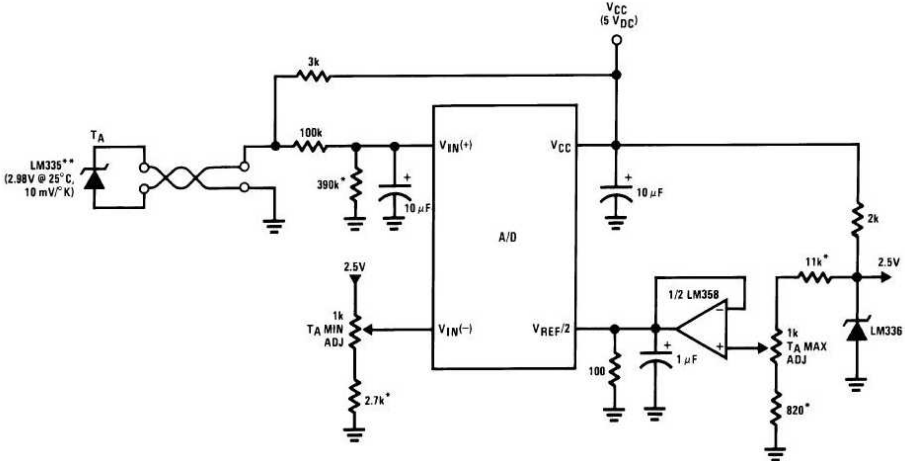
- ▶ Check the [online info](#)
- ▶ Non touch sensing







## µP Interfaced Temperature-to-Digital Converter



connecting to an ADC e.g. ADC0820 or ADC0801

# Humidity Sensor



- ▶ Check the [online document](#)
- ▶ Humidity range (RH) -> Capacitance
- ▶ BCcomponents 2322 691 90001: 10–90%RH Dc

## QUICK REFERENCE DATA

| PARAMETER                              | VALUE     | UI   |
|--|-----------|------|
| Humidity range (RH)                    | 10 to 90  | %    |
| Capacitance at +25 °C; 43% RH; 100 kHz | 122 ±15%  | pF   |
| Sensitivity between 12 and 75% RH      | 0.4 ±0.05 | pF/% |
| Frequency                              | 1 to 1000 | kHz  |
| Maximum AC or DC voltage               | 15        | V    |

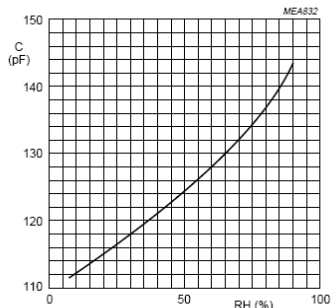
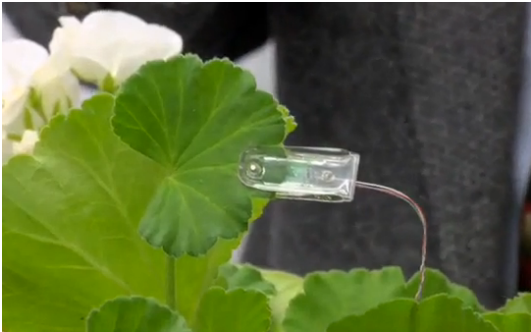


Fig.2 Typical capacitance as a function of relative humidity.

# Leaf Sensor Alerts When Plants Are Thirsty



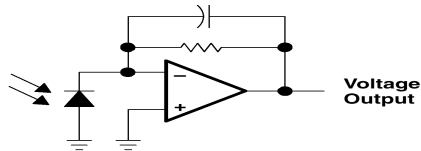
[https://youtu.be/VM4X\\_fqPPco](https://youtu.be/VM4X_fqPPco)



# Light-to-voltage Optical Sensors



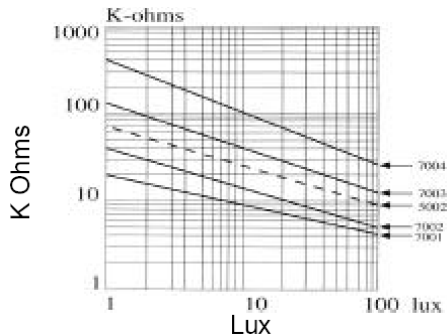
- ▶ Click the [online document](#)
- ▶ Light-to-voltage optical sensors, each combining a **photodiode** and an amplifier (feedback resistor = 16 MW, 8 MW, and 2 MW respectively).
- ▶ The output voltage is directly proportional to the light intensity on the photodiode.



# CdS Photoconductive Photocells



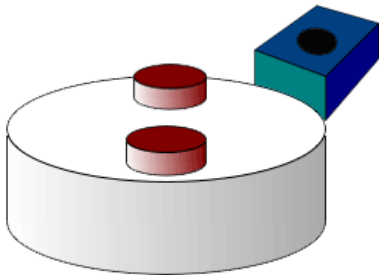
- ▶ Click the [online document](#)
- ▶ Cadmium Sulfoselenide (CdS)
- ▶ Light sensing using CdS



## 3-4. Hall effect Sensors



- ▶ voltage difference across an electrical conductor, transverse to an electric current
- ▶ A wheel containing two magnets passing by a [Hall effect sensor](#)



# Application on Magnetic levitation



Magnetic levitation Train Model: [https://youtu.be/TeS\\_U9qFg7Y](https://youtu.be/TeS_U9qFg7Y)



frog levitation <https://youtu.be/A1vyB-05i6E>

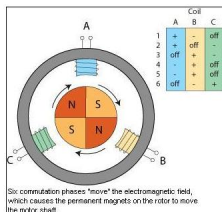


<https://youtu.be/XjjBqzilkIc>

# Hall effect sensors and brushless DC motors



## Brushless DC motor

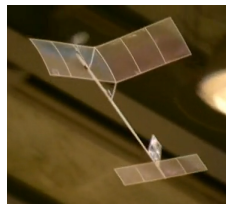


<https://youtu.be/bCEiOnuODac>

Is it using Hall effect sensor? Don't know.



<https://youtu.be/cm0h2Qf3upQ>



<https://youtu.be/JmRkxZT4XhY>

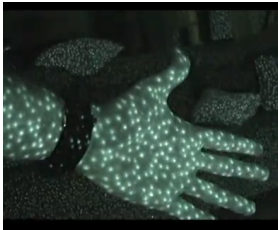
# 3-5. Kinect Sensors



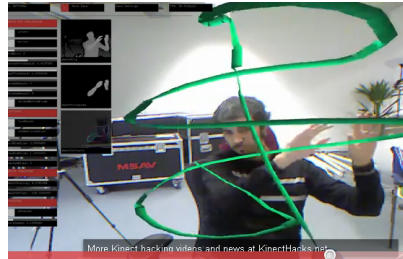
<https://learn.adafruit.com/hacking-the-kinect>



<https://youtu.be/p2q1HoxPioM>



<https://youtu.be/nvvQJxgykcU>



<https://youtu.be/Brpu30vjCa4>

# Summary



- ▶ Studied the characteristics of various sensors
- ▶ and their applications