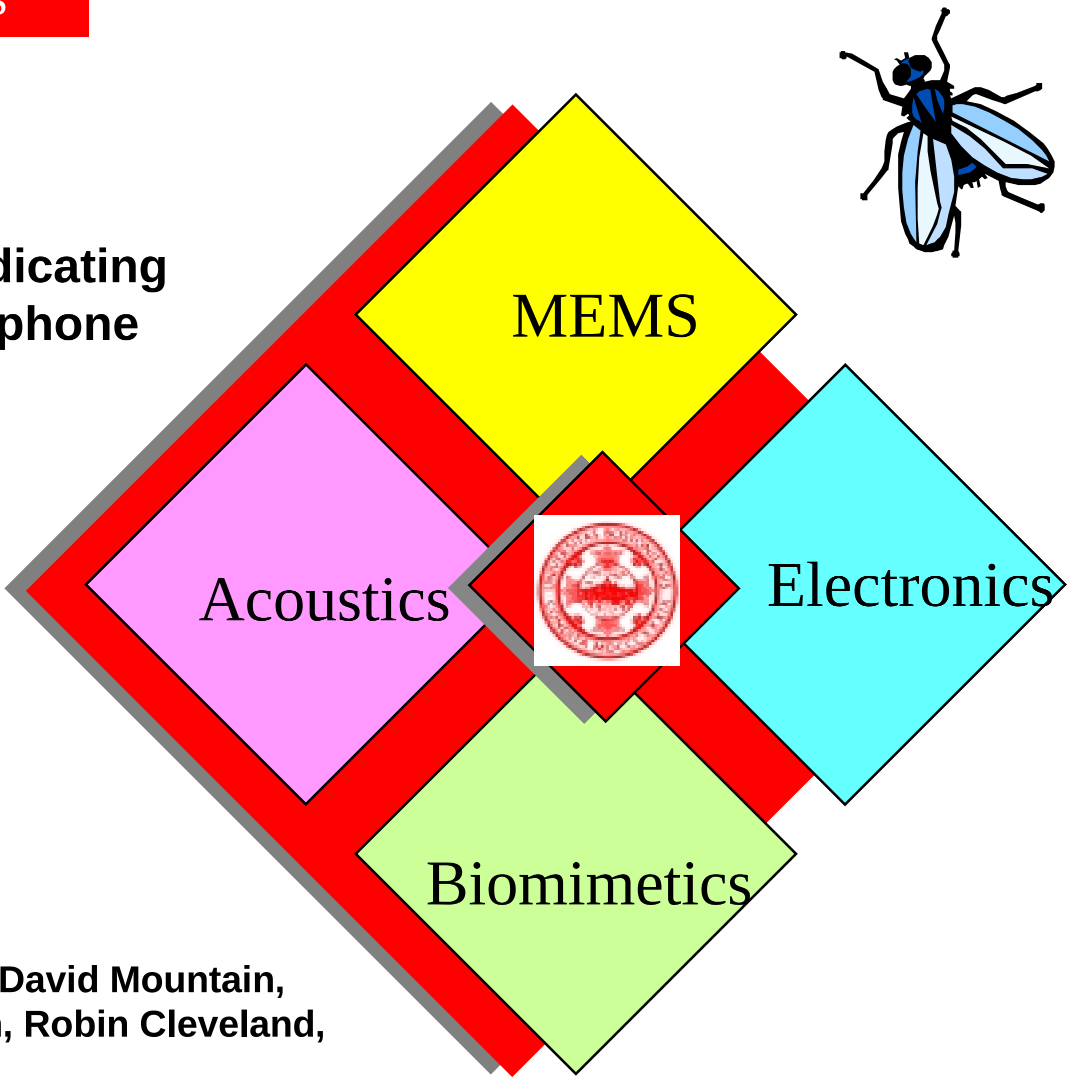
B.U.G.S.: Acoustics

Possibility of a direction-indicating low frequency MEMS microphone



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with acknowledgments to

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DARPA

BOSTON UNIVERSITY
GROUP FOR SENSORS

Report Documentation Page

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14. ABSTRACT

15. SUBJECT TERMS

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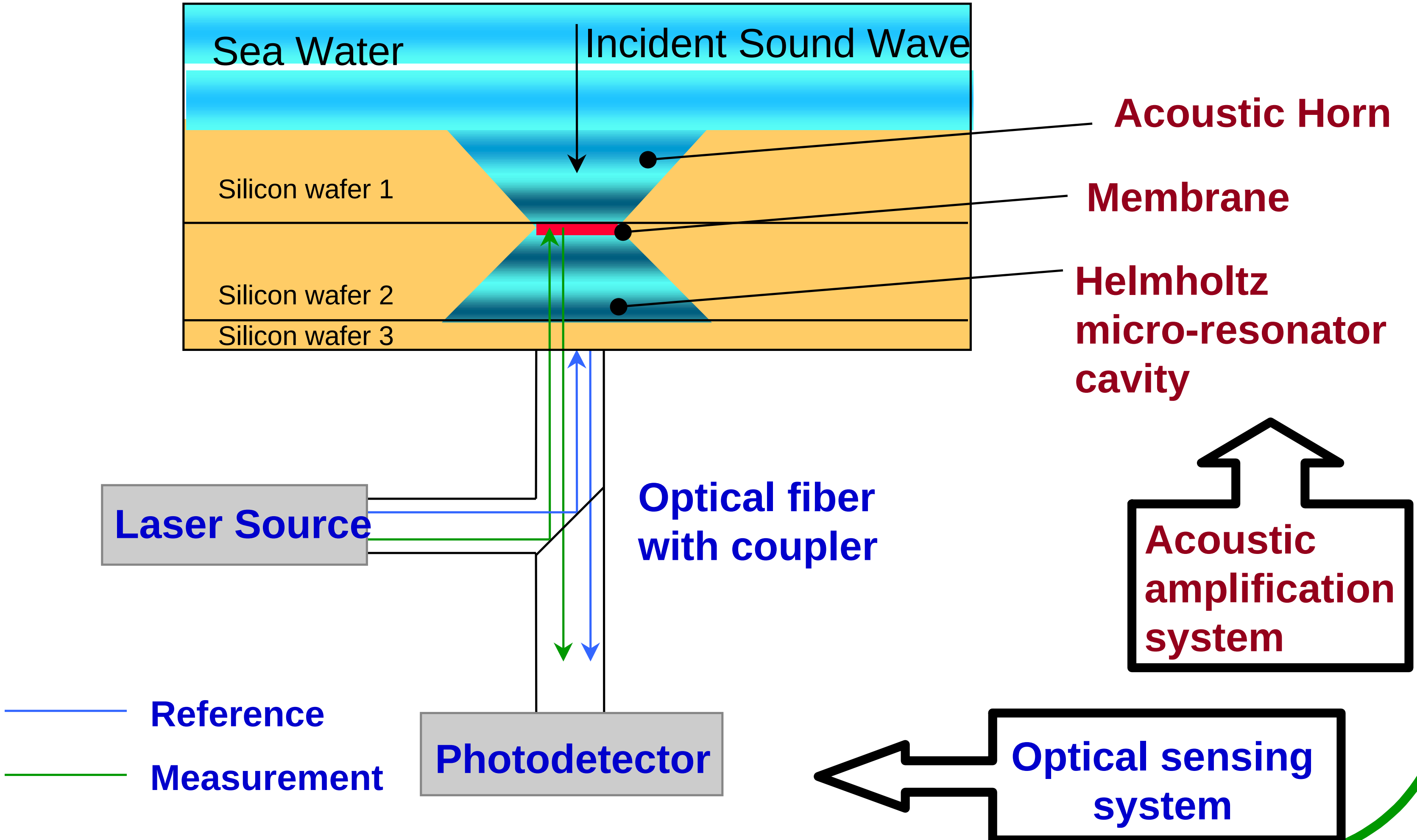
Boston University MEMS Hydrophone (currently under development)



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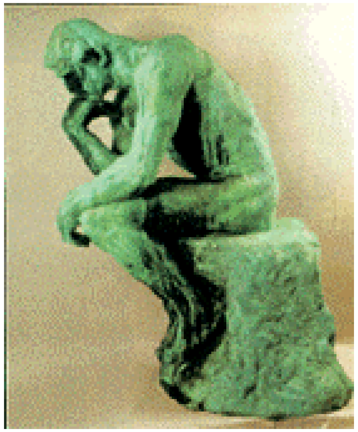
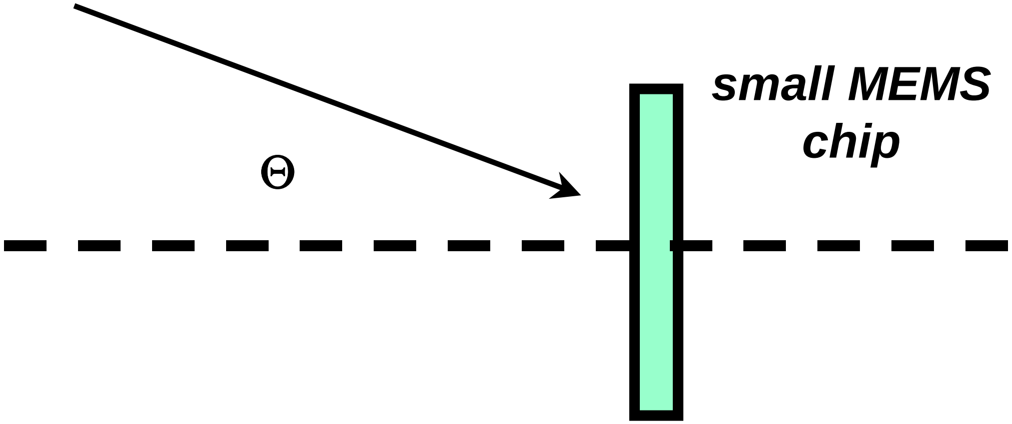
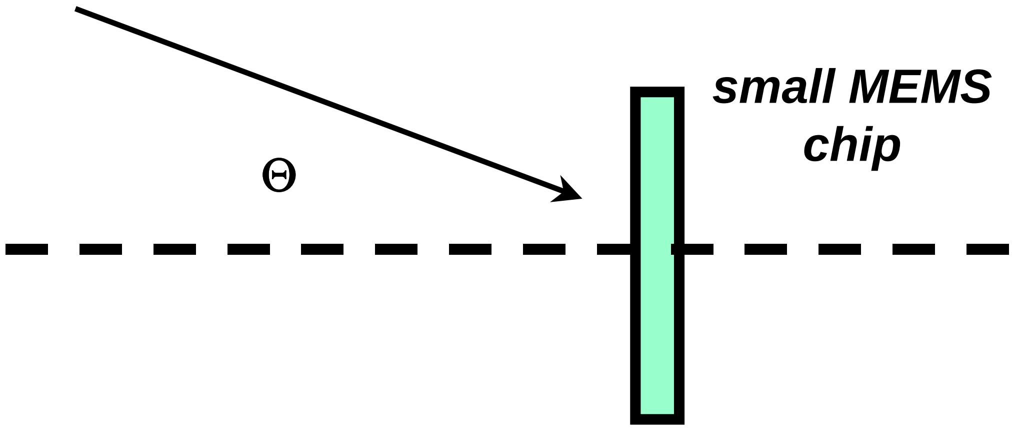
Issue:

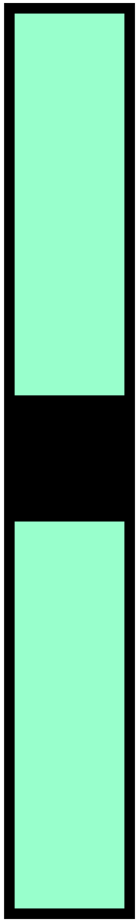
Can we build a compact MEMS device that senses acoustic signals in the lower kilohertz range and which nevertheless gives us a good indication of the direction from which the sound is coming?





What we can do for sure:



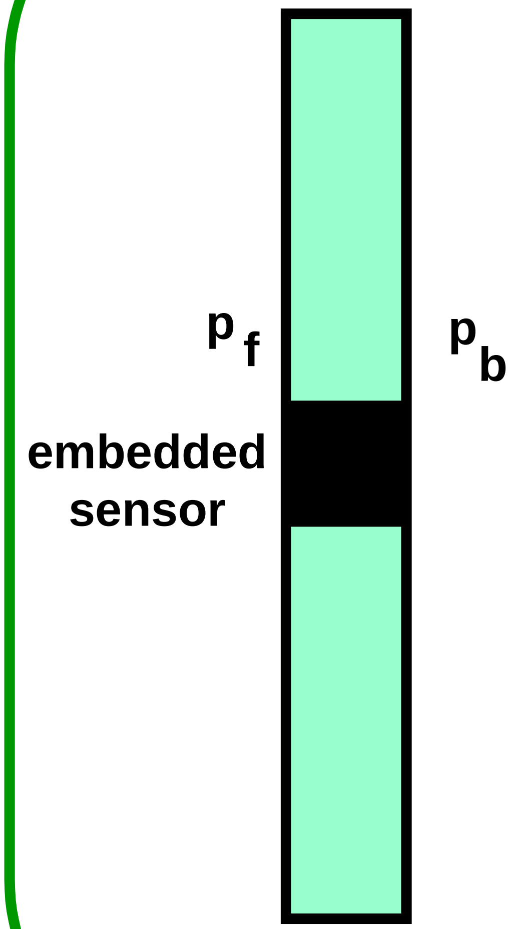


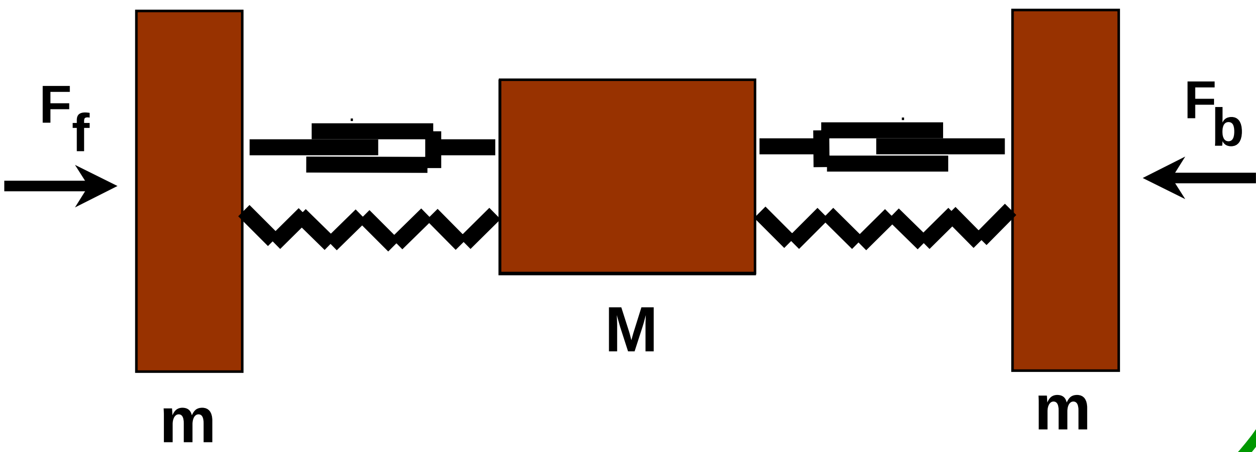
We can design a sensor embedded in the chip which will tell you very reliably *when*

$$\Theta = 0$$

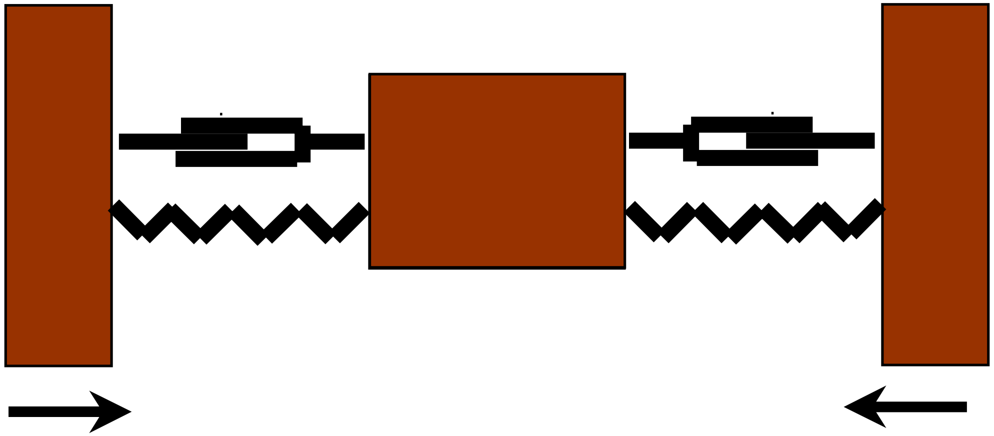
$p_f \approx p_b$, **but** $p_f \neq p_b$

Heuristic mechanical model of the embedded sensor

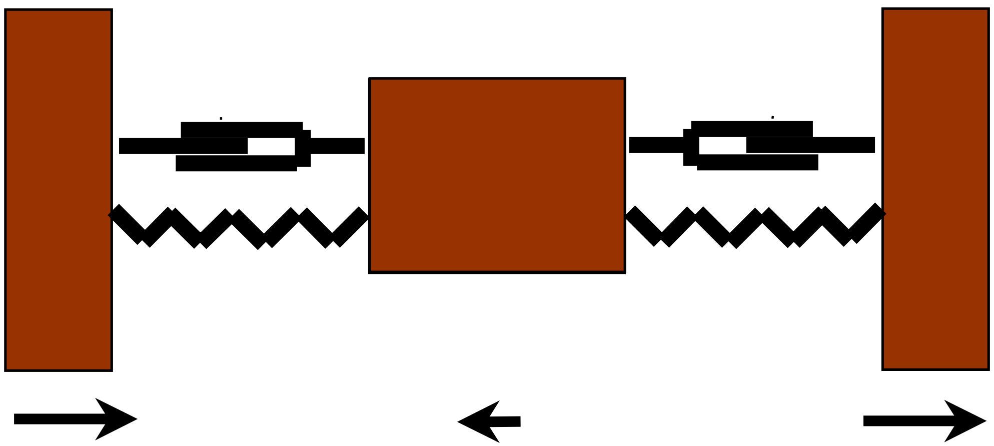




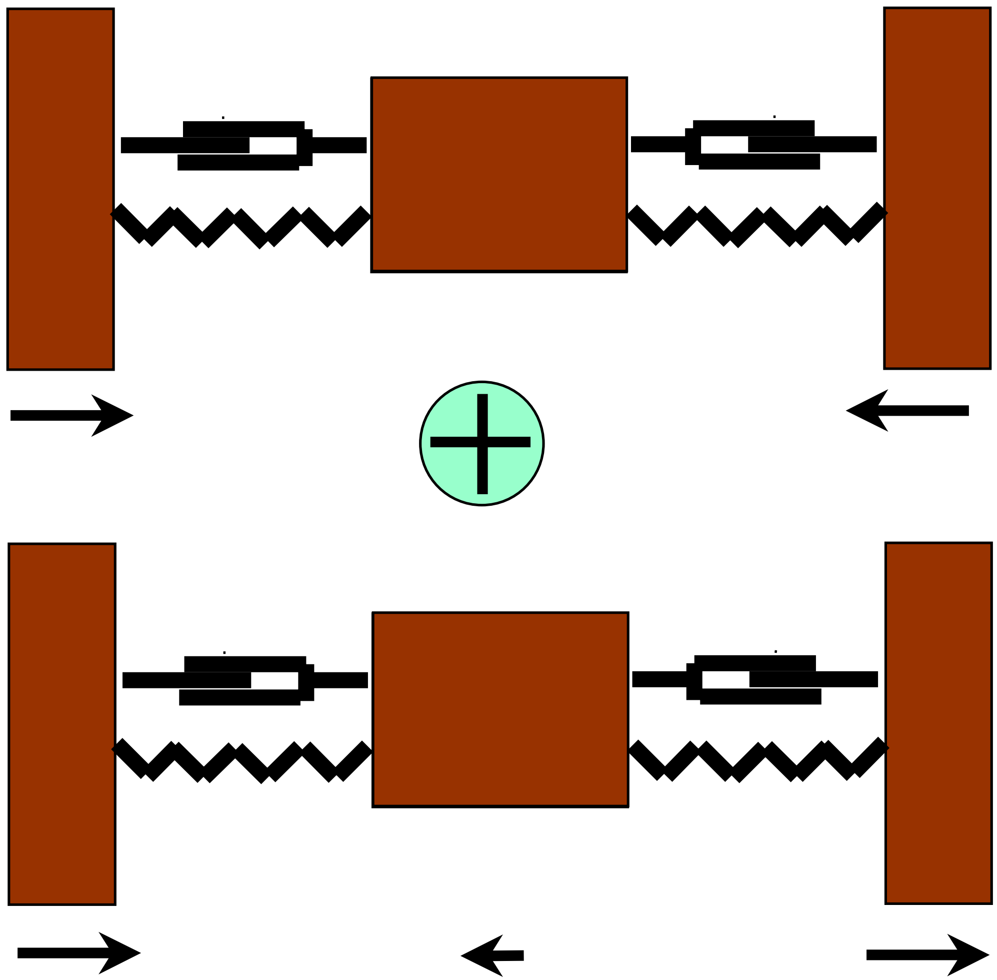
Natural resonance modes



Both faces moving inward (or outward) simultaneously



Both faces moving in the same direction with the same amplitude simultaneously



It is possible to excite the system

so that the relative amplitudes and phases of the two modes

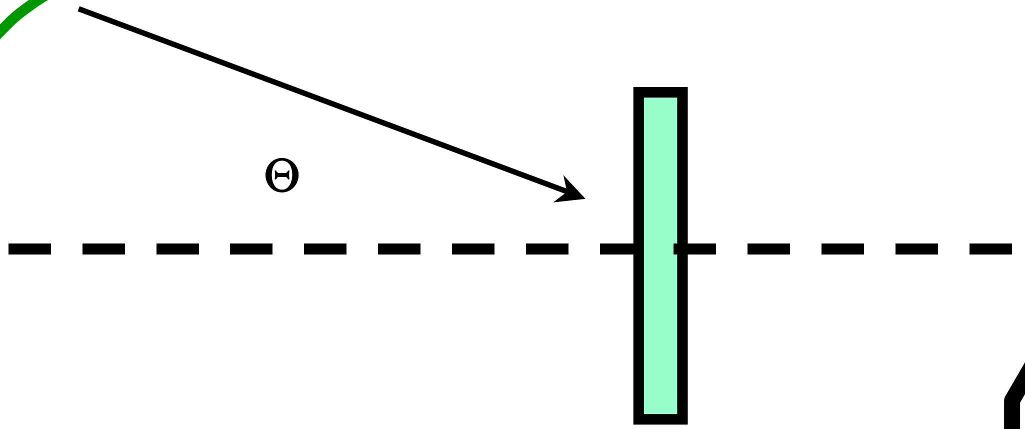
are such that

the back face of the sensor

doesn't move at all

Design strategy:

Choose parameters so that this excitation corresponds to Θ=0 for the frequency range of interest



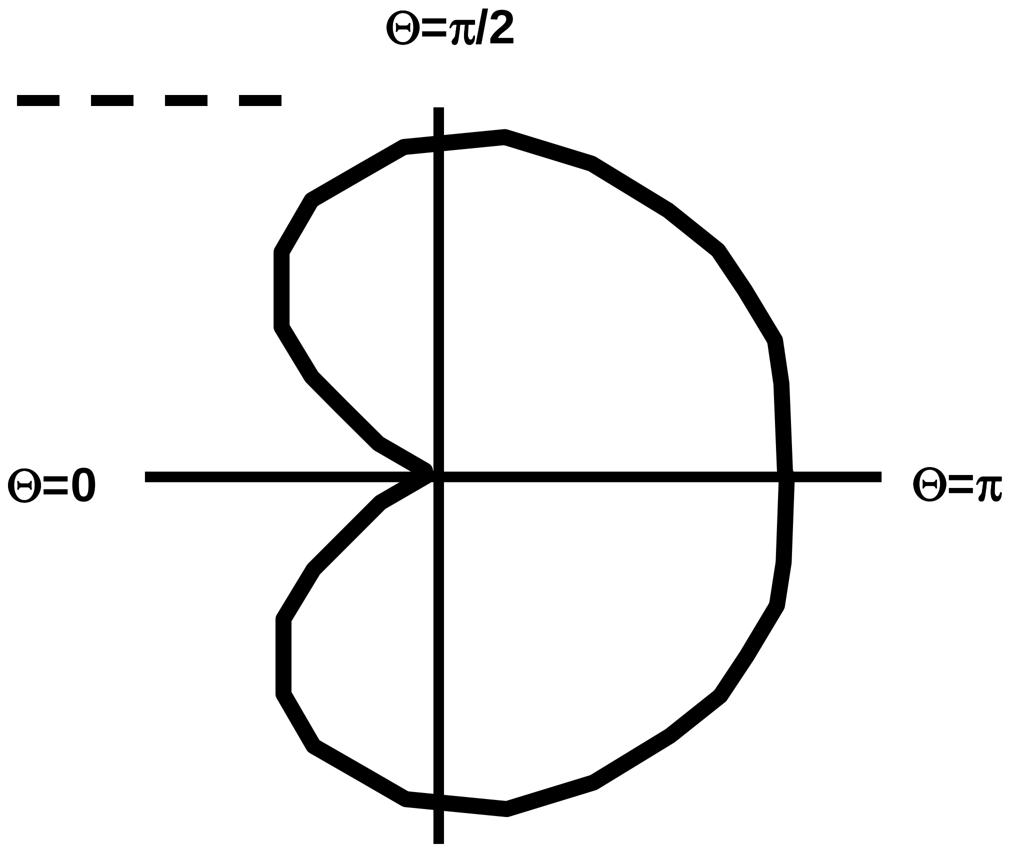
Polar plot:

Radial coordinate corresponds to

vibration amplitude of

back face of

embedded sensor



Comments on possible realizations and extensions

- Frequency range must be close to resonance frequency of non-squeezing mode
- For fixed chip orientation, azimuth direction determination requires array with some minimum lateral distance requirement
- Can design systems with rotatable chips; rotate until $\Theta=0$ is indicated
- Several sensors on same chip possible, each corresponding to a different choice of Θ, different frequency range