



**GUC**  
German University in Cairo

# CAPACITIVE FORCE SENSOR

**ANN EZZAT  
PAULA MAGDY**

**PRESENTED BY:  
ANTHONY USSAMA  
SALMA ESSAM**

**JOSEPH MAHER  
SOMAYAH MANSOUR**

# CONTENT

- 1      INTRODUCTION**
- 2      METHODOLOGY**
  - 2.1    THEORETICAL ANALYSIS**
  - 2.2    EQUATION OF MOTION**
  - 2.3    LINEARIZATION USING 555 TIMER**
  - 2.4    LINEARIZATION USING OP-AMP**
  - 2.5    LINEARIZATION USING OP-AMP AND POWER AMPLIFICATION CIRCUIT**
- 3      RESULTS**
- 4      CONCLUSION**

# INTRODUCTION

# OBJECTIVE



Converting physical applied forces  
into measurable changes in  
capacitance.



# FUNCTIONALITY OF THE SENSOR

## Materials & Components

Housing material is  
ABS 3D printing  
Copper capacitive  
plates

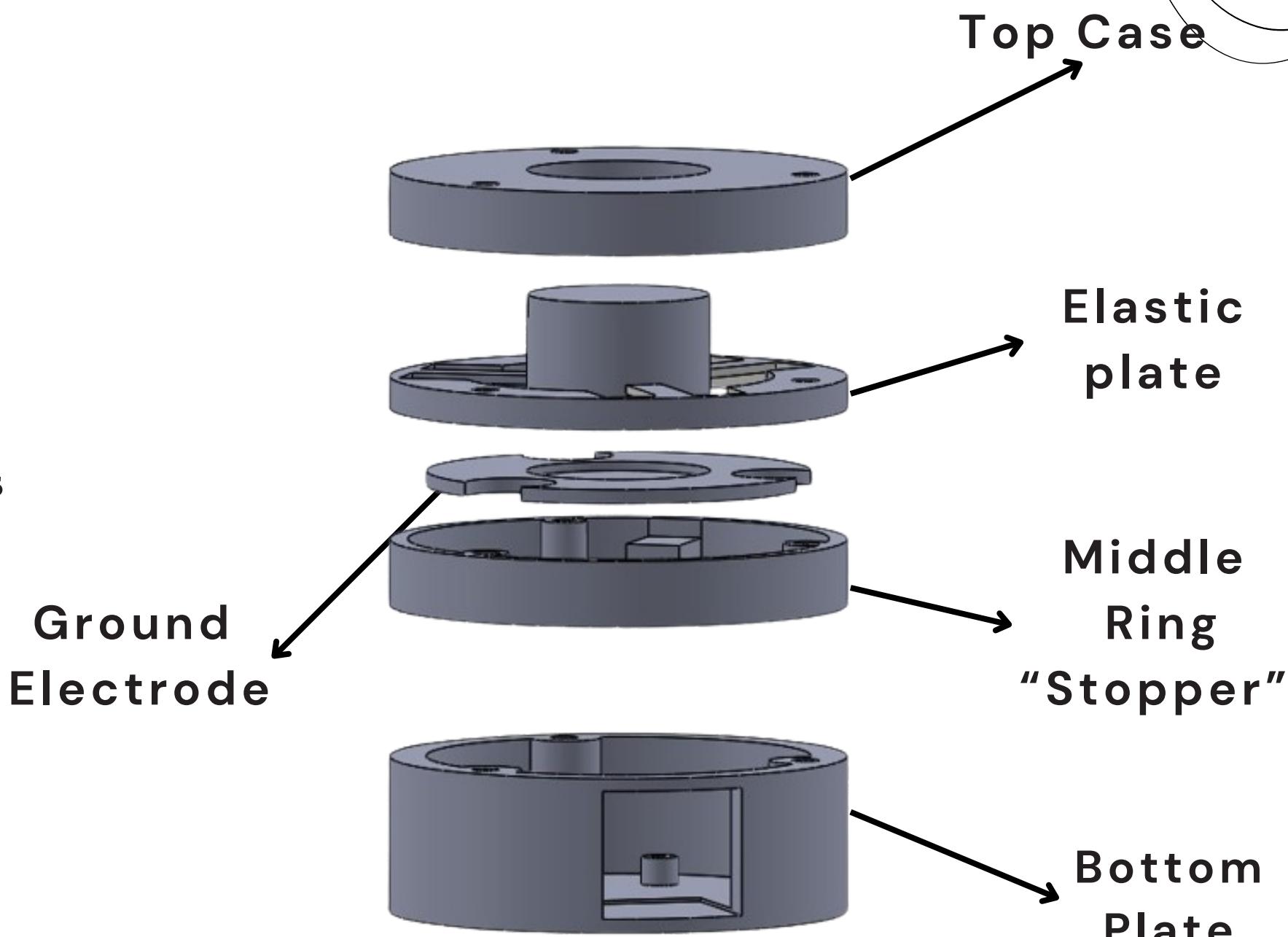
Dielectric material: Air

## Dimensions

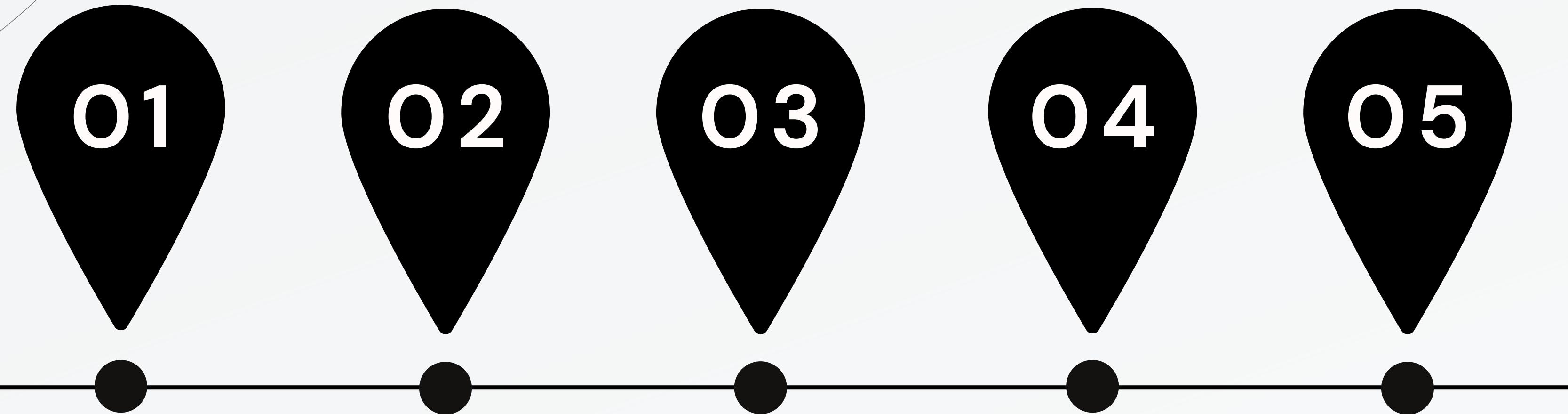
Outer Diameter: 50mm  
Inner Diameter: 20mm  
Height: 36.75mm  
Distance between 2 plates  
5.65mm

## How it works

Measuring voltage change  
after force application to  
determine sensor's static and  
dynamic characteristics.



# METHODOLOGY



THEORETICAL  
ANALYSIS

EQUATION OF  
MOTION

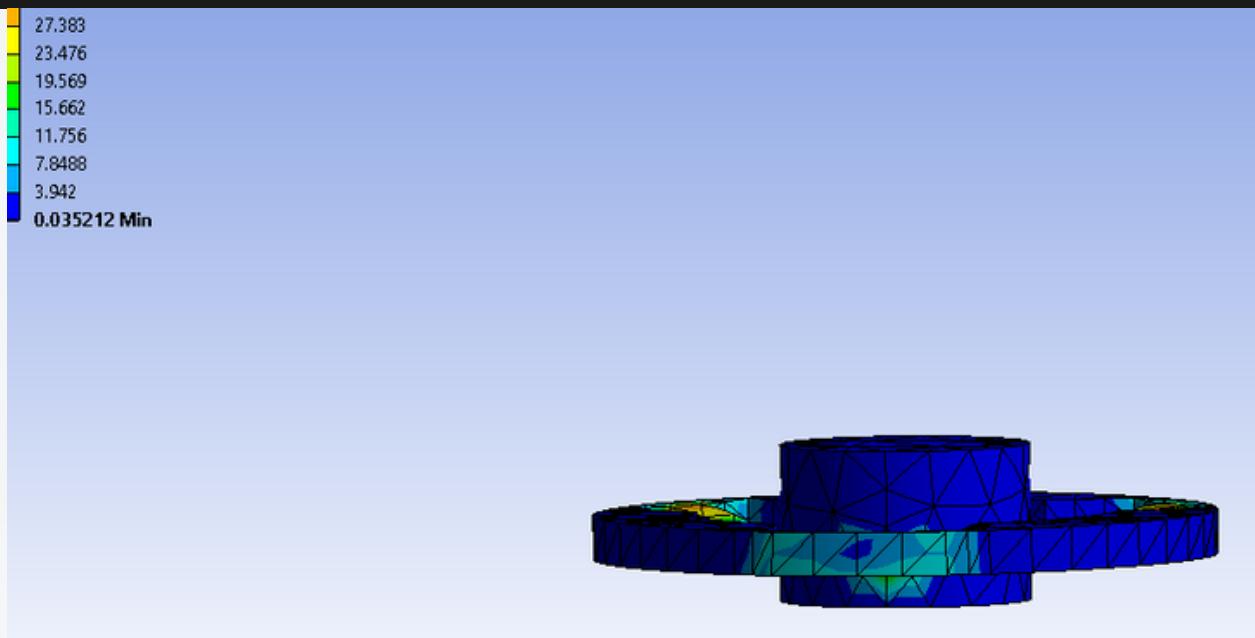
LINEARIZATION  
USING 555  
TIMER

LINEARIZATION  
USING OP-AMP

LINEARIZATION  
USING OP-AMP  
AND POWER  
AMPLIFICATION  
CIRCUIT

# THEORETICAL ANALYSIS

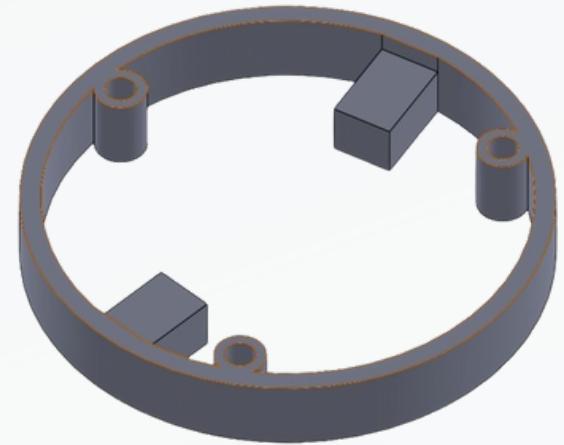
## ANSYS Simulations on elastic element



Through Ansys software, we simulated the deflection of the ABS elastic element.

- Safety Factor = 1.1365

- The cantilever beam's maximum deflection was calculated to be 2.02 mm.
- Stoppers were added to prevent further deflection.



## Calculations

$$\frac{\delta_{y\max}}{\sigma_{\max}} = \frac{2L^2}{3EH}$$

# EQUATION OF MOTION

## Mechanical Model

$$T = \frac{1}{2}m\dot{x}^2$$

$$V = \frac{1}{2}kx^2$$

$$D = \frac{1}{2}b\dot{x}^2$$

$$m\ddot{x} + b\dot{x} + kx = f(t)$$

The Lagrangian method is utilized for determining the equation that governs a mechanical system.

- $f(t)$ : Acting Force
- $m$ : 5.5 grams (+load)
- Spring constant  $k$ : 1157.4 N/m
- Damping Coefficient  $b$ : 0.602

# EQUATION OF MOTION

## Electrical Model

$$V = \frac{1}{2} \frac{1}{C} q^2 = \frac{1}{2} [C1 + Cmeasuresd] V_c^2$$

$$D = \frac{1}{2} R \dot{q}^2 = \frac{1}{2} R [C1 + Cmeasuresd^2] \dot{V}_c^2$$

$$R [C1 + Cmeasuresd^2] \dot{V}_c + [C1 + Cmeasuresd] V_c = f(t)$$

The Lagrangian method is utilized for determining the equation that governs an electrical system.

- Since the L is very small, the kinetic energy is neglected of the ease of calculations
- $f(t)$ : Acting Force
- $C1 = 1 \text{ pF}$
- Resistance  $R = 35.4 \text{ Kohms.}$

# **LINEARIZATION USING 555 TIMER**

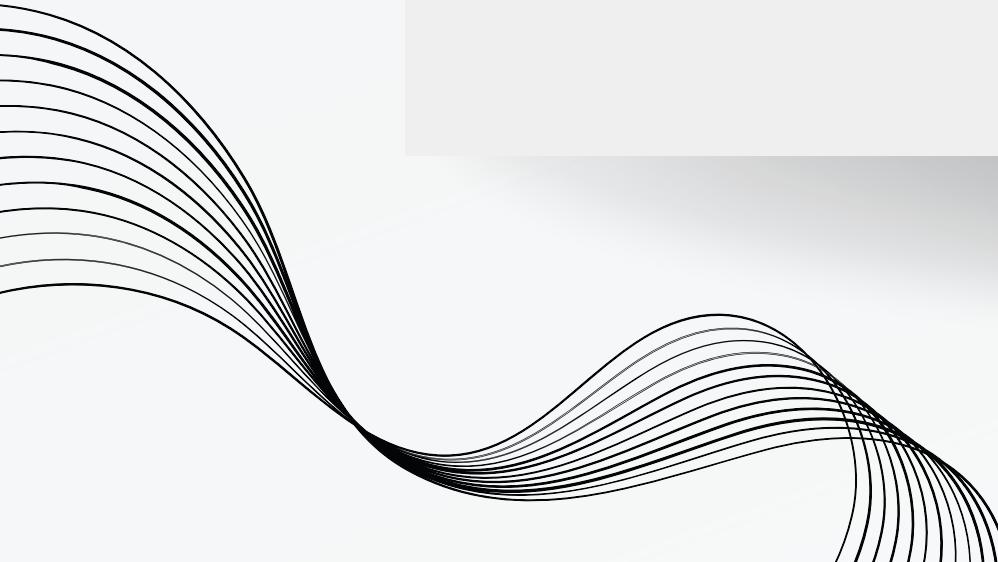
**The device possesses two main features: the capacity to read capacitance and the ability to generate a square wave.**

**However, one of its limitations is its insensitivity to small changes in capacitance. It can not detect changes of less than 1 pF with a high degree of fluctuation, which makes it unsuitable for applications that require high levels of precision.**

# LINEARIZATION USING OP-AMP

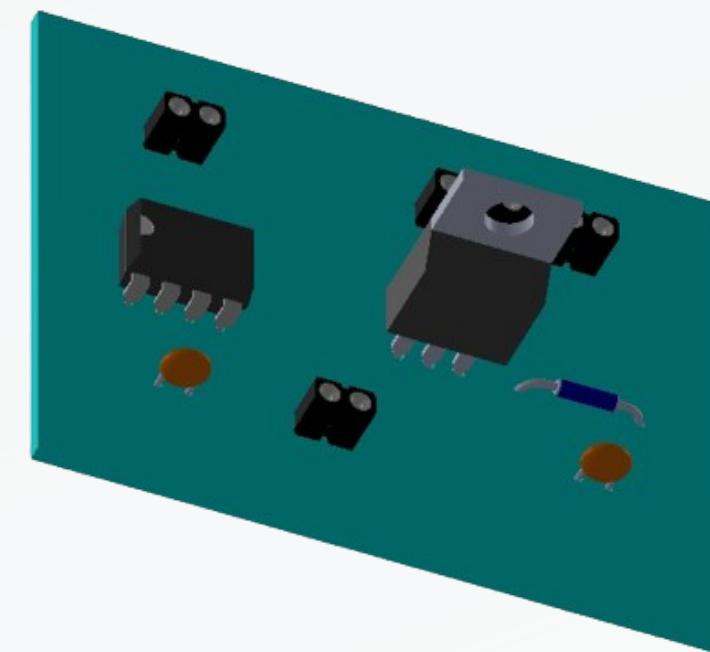
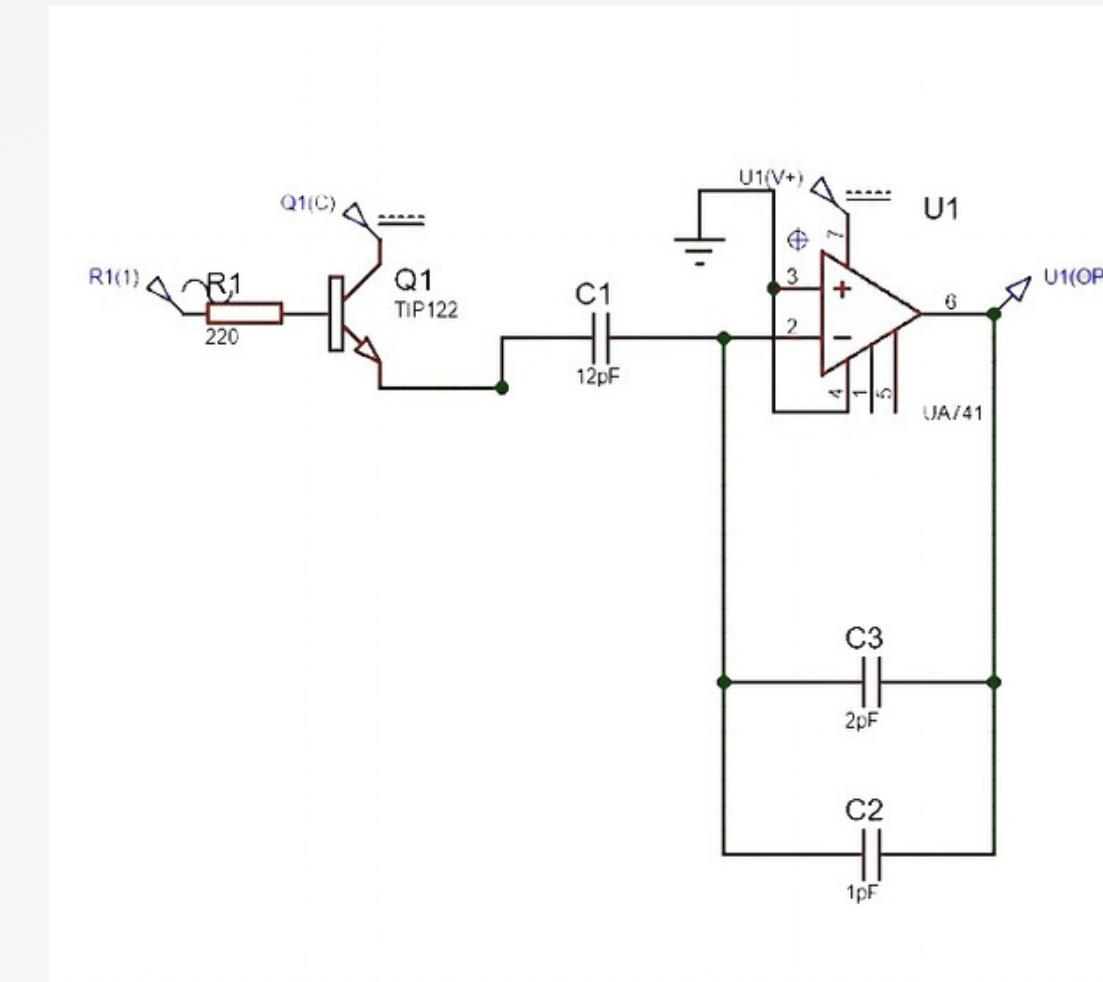
The main problem was that current did not flow in the circuit when capacitance was in the pF range so there was no output.

- No change in capacitance
- No current flow
- No output voltage



# LINEARIZATION USING OP-AMP AND POWER AMPLIFICATION CIRCUIT

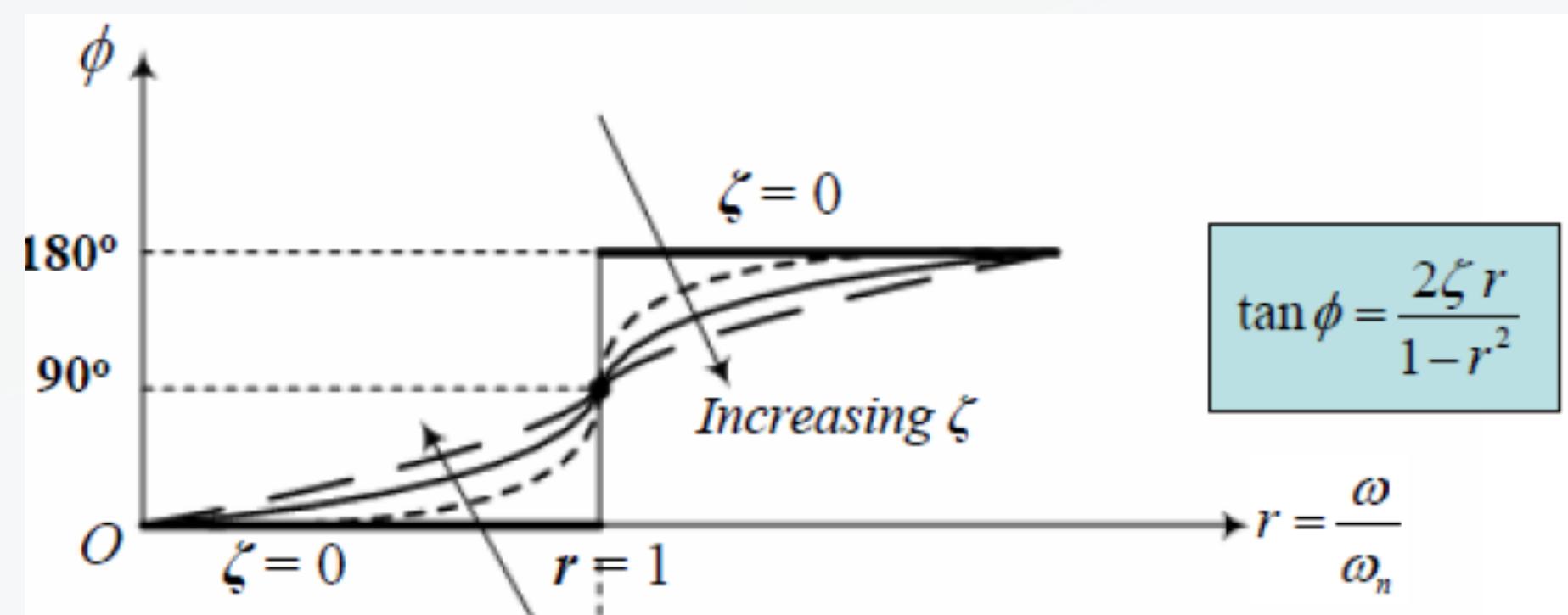
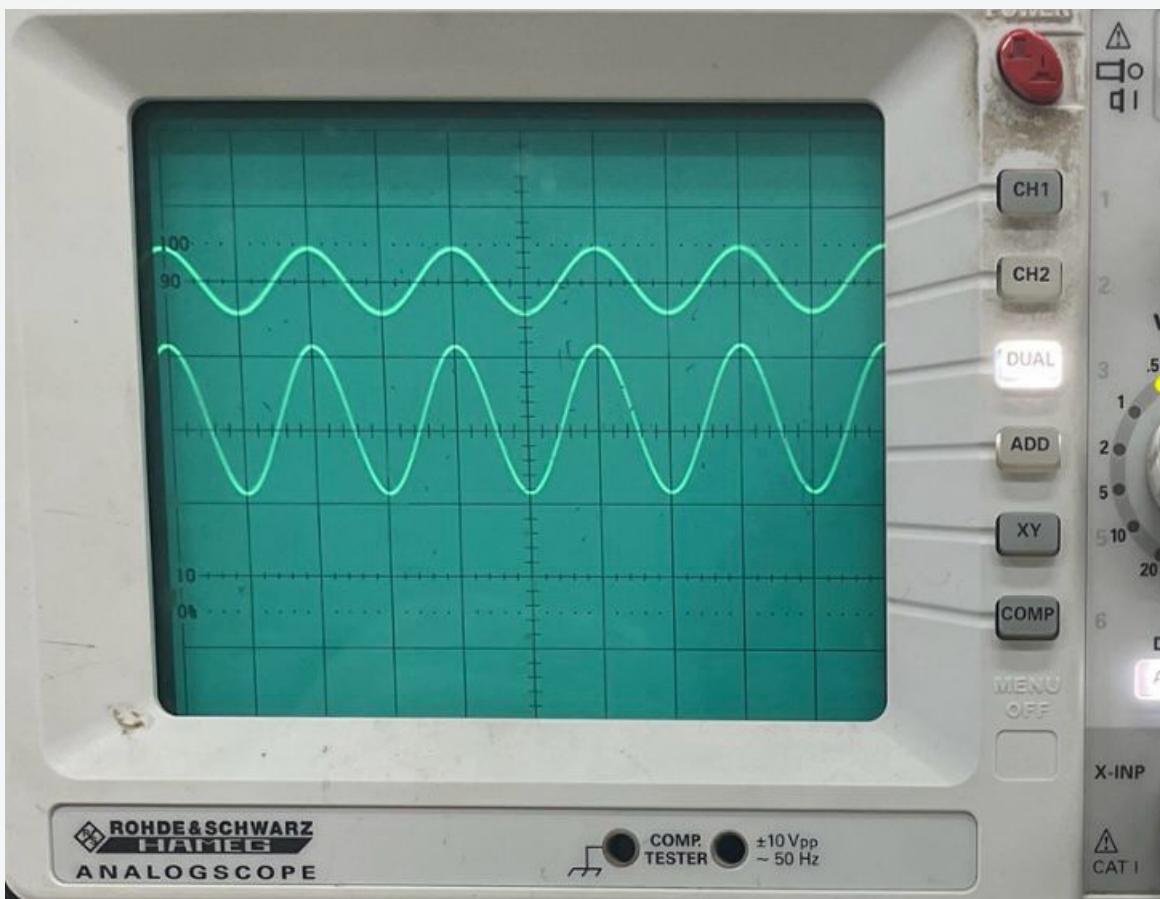
To achieve system linearization, a power amplification circuit utilizing the *IRF Z44N* was employed. This circuit was instrumental in augmenting the current supplied to the op-amp circuit, thereby facilitating accurate readings.



# RESULTS

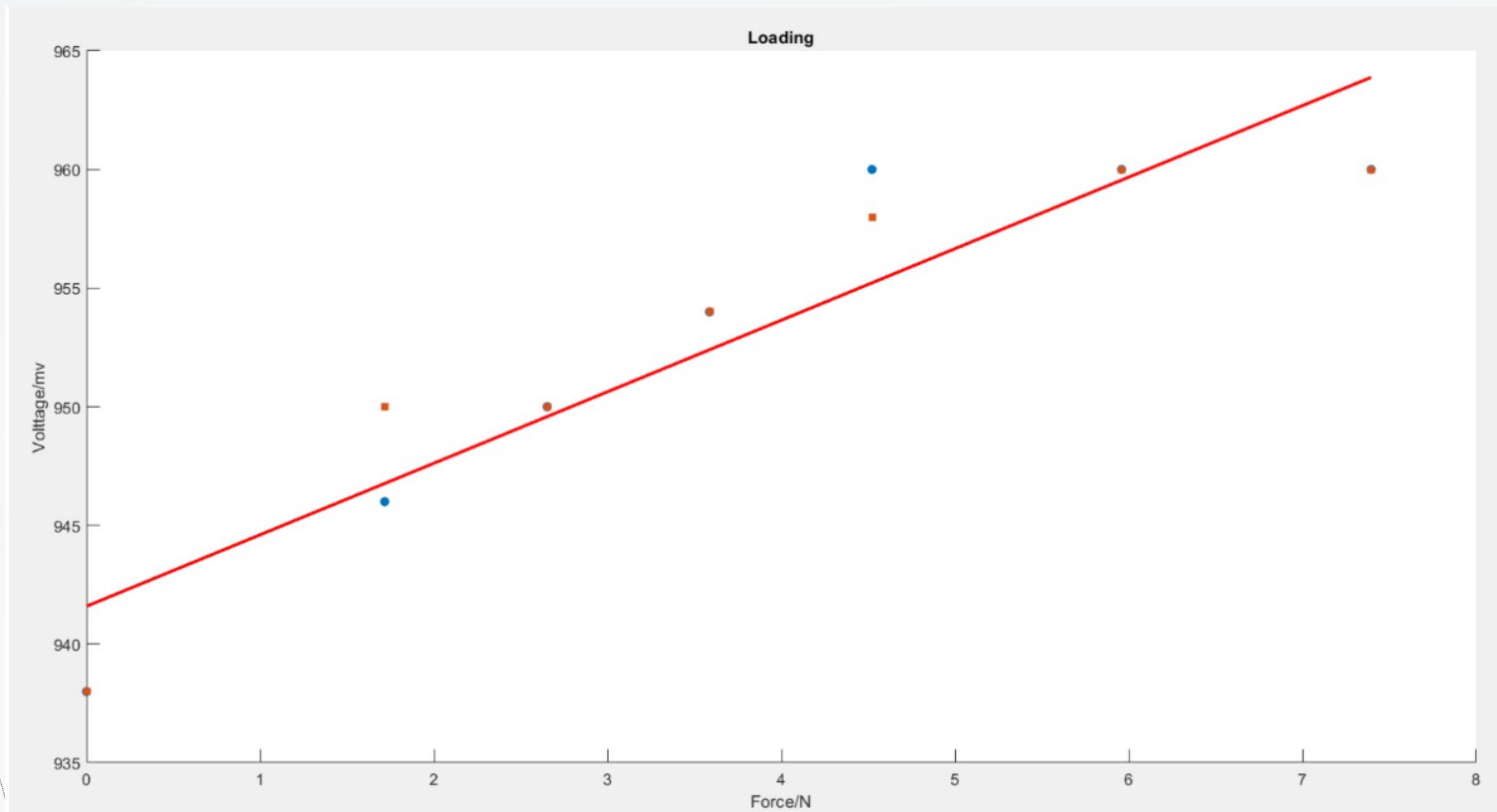
# OUTPUT READINGS

Input Frequency = 120 KHz  
Natural frequency = 73 Hz.



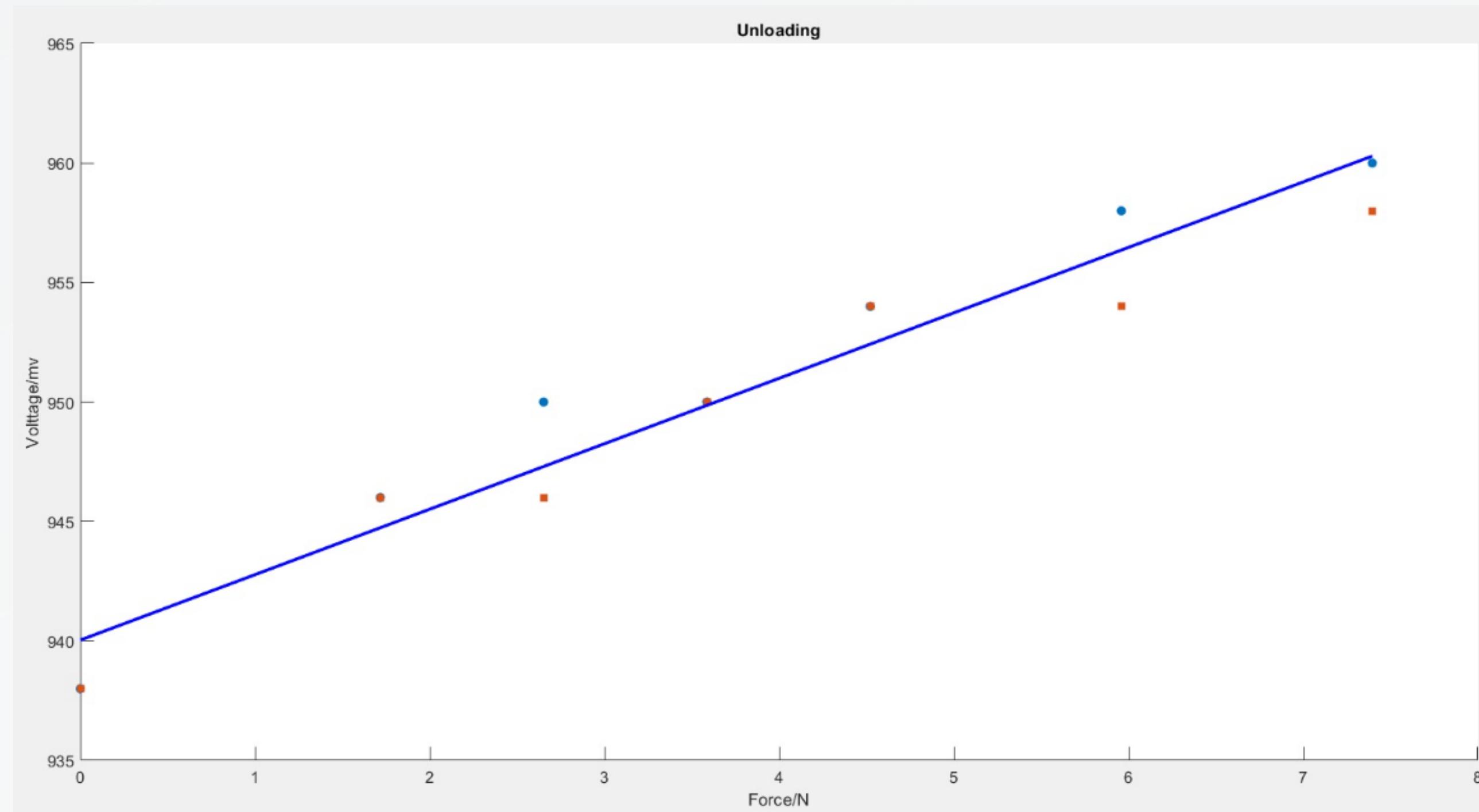
# STATIC CHARACTERISTICS

Calibration curve analysis was performed during the loading of weights onto the sensor.



# STATIC CHARACTERISTICS

Calibration curve analysis was performed during the unloading of weights onto the sensor.



# STATIC CHARACTERISTICS

*Sensitivity*  
Assessment

$$S = \Delta V / \Delta F$$
$$S = 3 \text{ mV/N}$$

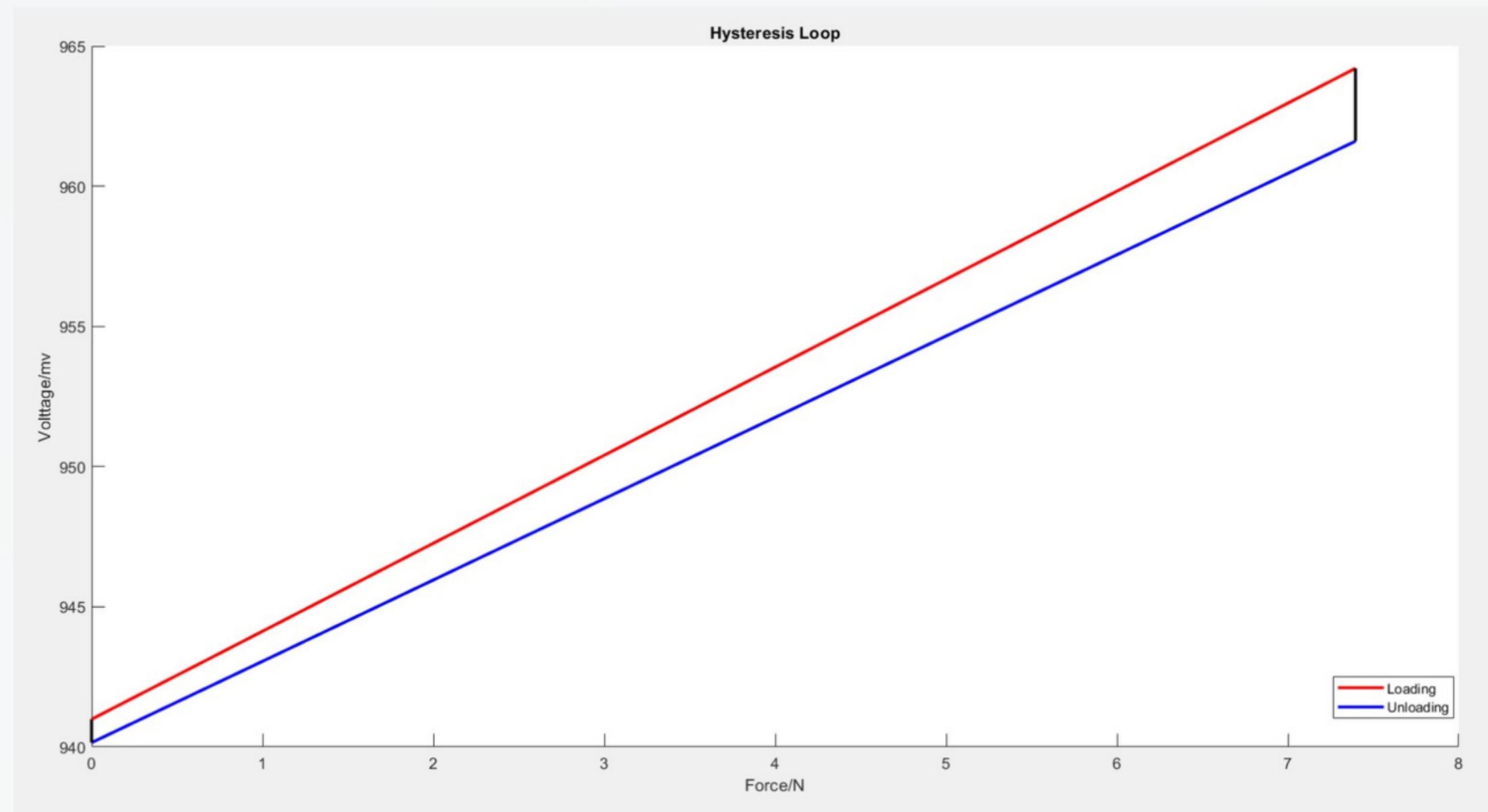
*Resolution*  
0.93 N

*Range*

The operational range  
of the sensor is from  
0.93 N to 6.8 N

# STATIC CHARACTERISTICS

Hysteresis = 7.73%



# DYNAMIC CHARACTERISTICS

*Second Order  
System*

*Underdamped*

*Step Input*



# SECOND ORDER EQUATION

$$\frac{a_2}{a_0} \frac{d^2y(t)}{dt^2} + \frac{a_1}{a_0} \frac{dy(t)}{dt} + y(t) = \frac{b_0}{a_0} x(t)$$

where,

$$a0 = 1157 \text{ N/m}$$

$$a2 = 5,5 \text{ g}$$

$$bo = 3471$$

$$a1 = 0.19$$

# FREQUENCY RESPONSE

$$\delta = 0.038$$

$$w_d = 72.9 \text{ Hz}$$

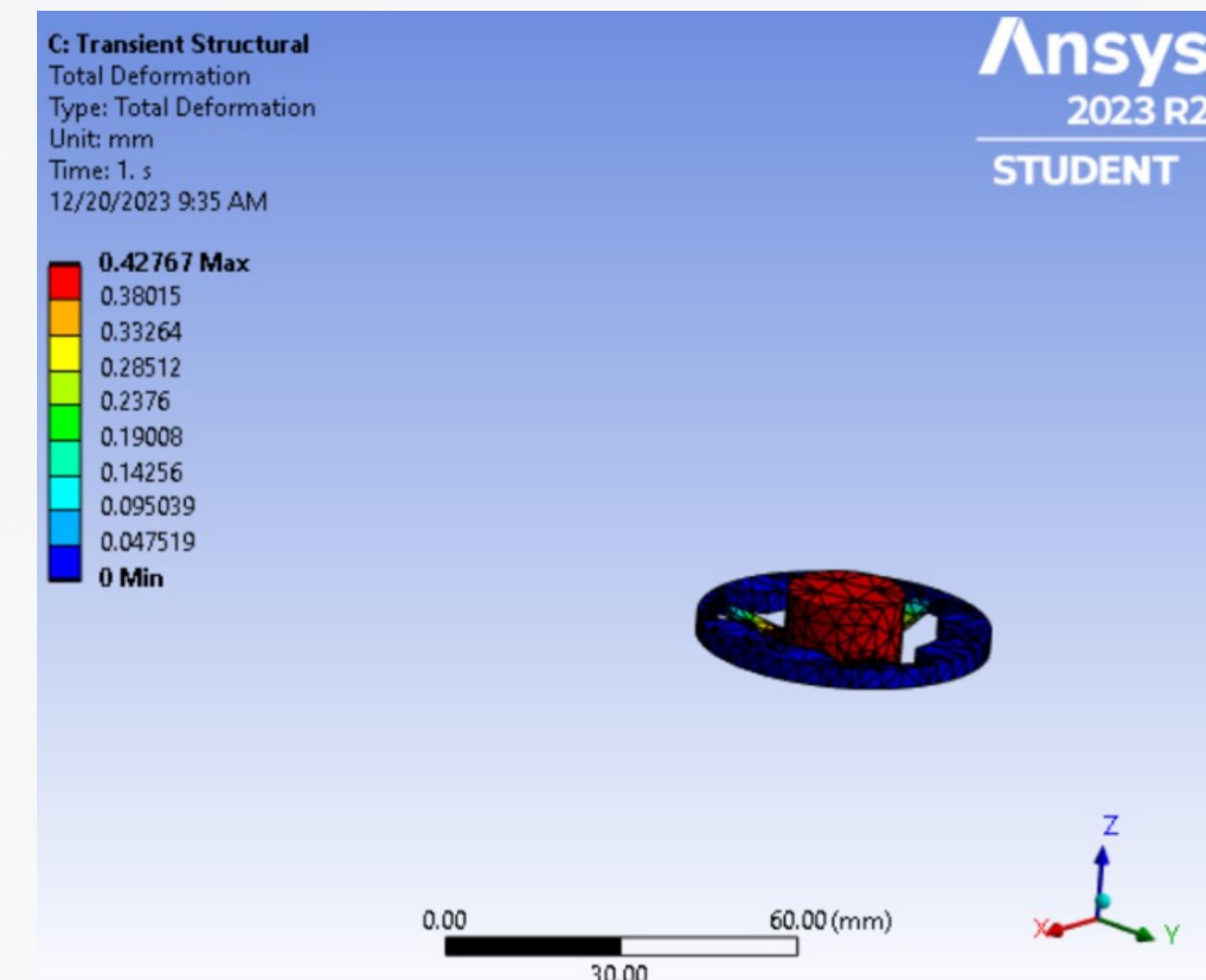
$$\text{Rise Time} = 1.23\text{s}$$

$$\text{Maximum Overshoot} = 0.887$$

$$\text{Peak Time} = 0.043\text{s}$$

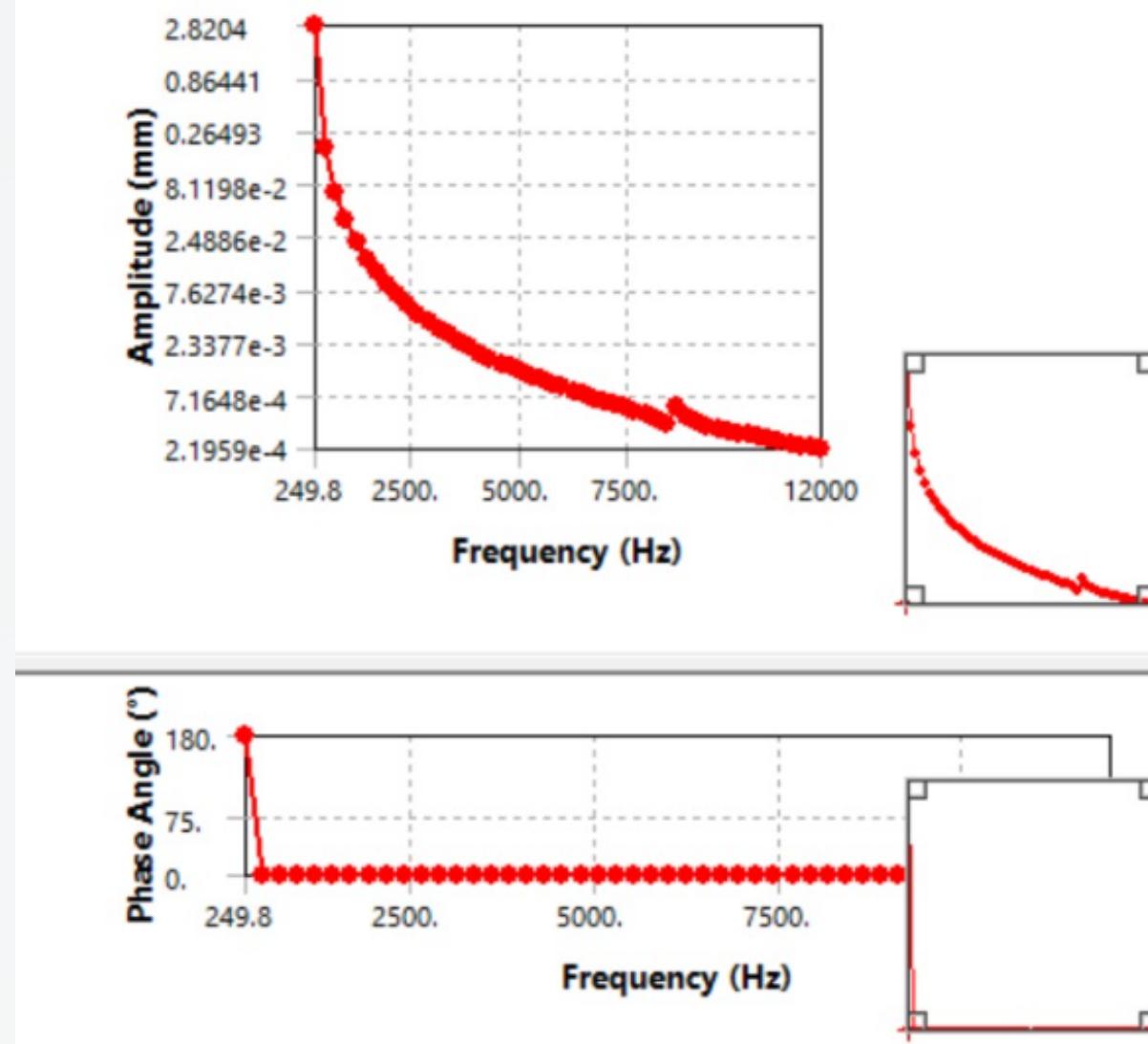
$$\text{Resonance Frequency} = 72.9$$

$$\text{Resonance Amplitude} = 13.167$$



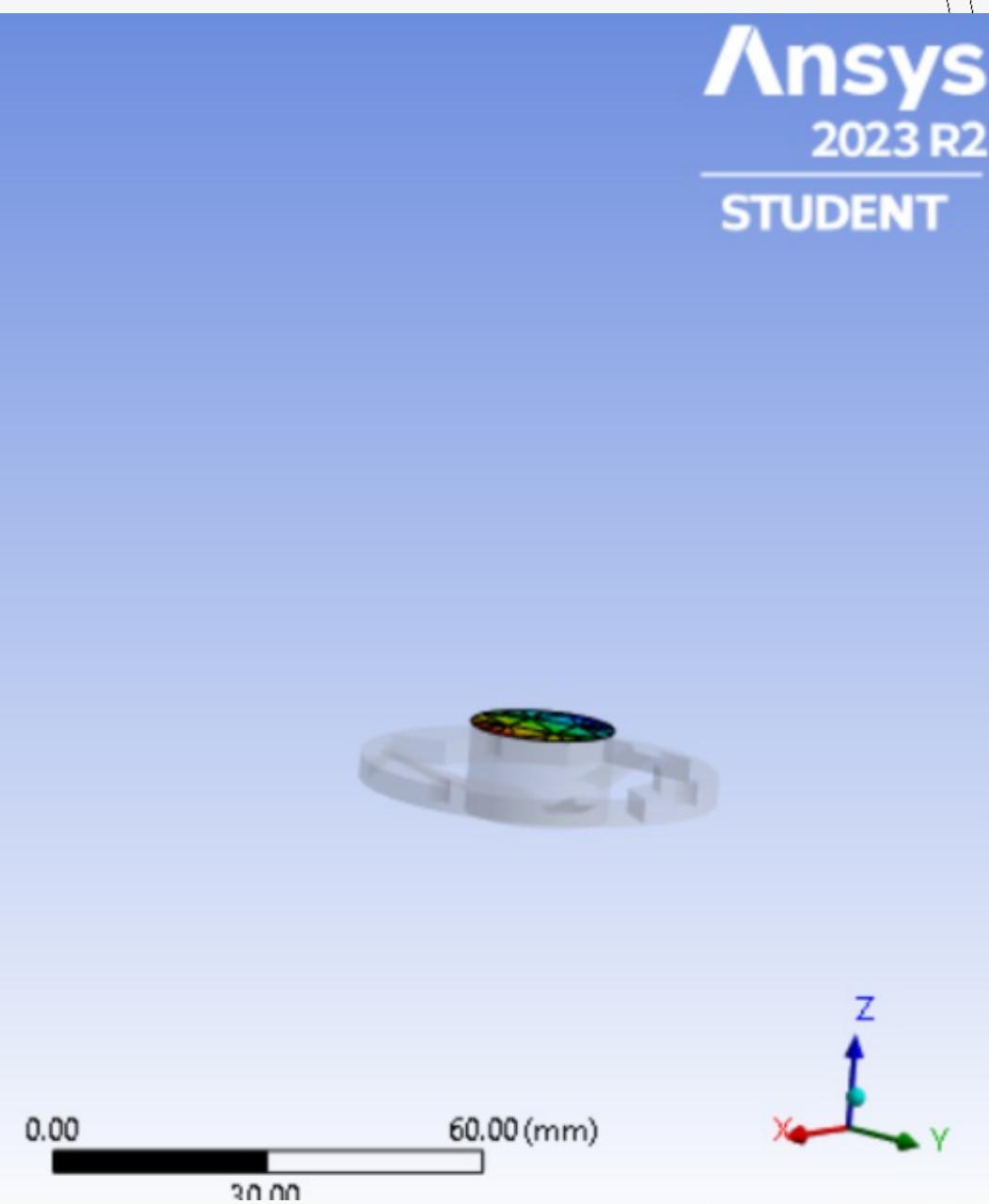
# FREQUENCY RESPONSE

Frequency Response



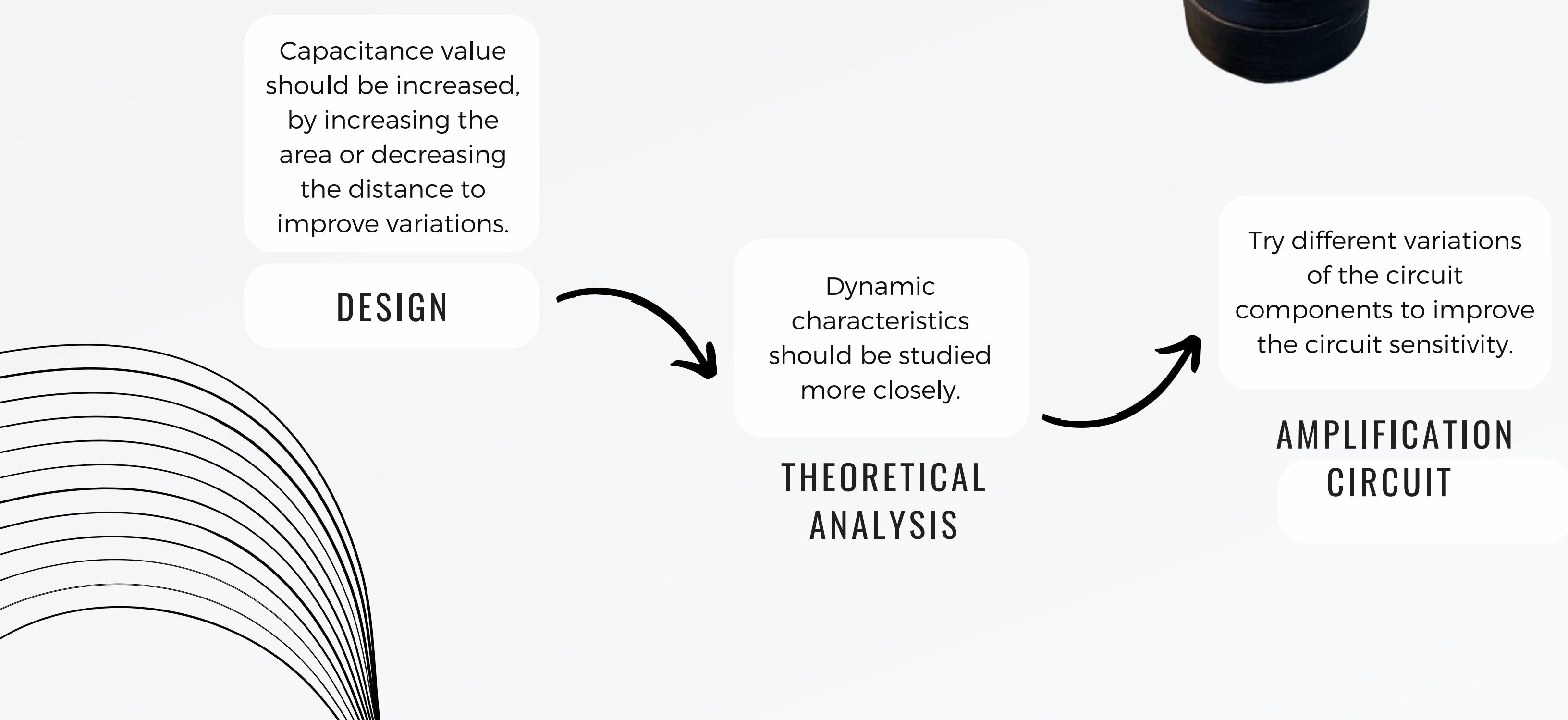
C: Transient Structural  
Total Velocity  
Type: Total Velocity  
Unit: mm/s  
Time: 1. s  
12/20/2023 9:36 AM

8.2962 Max  
8.2862  
8.2761  
8.2661  
8.256  
8.246  
8.2359  
8.2259  
8.2159  
8.2058 Min



# CONCLUSION

# FUTURE WORK





**THANK YOU  
FOR YOUR  
ATTENTION**

