
mTouch™ Capacitive Sensing Using Period Method

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INTRODUCTION

This application note is an addendum to the information in the previous capacitive touch sensing application notes, found on Microchip's web site. It builds specifically on AN1101, "Introduction to Capacitive Sensing". This application note focuses on how to use either an SR latch enabled part, or our new family of parts with a dedicated Cap Sense Module (CSM) to measure changes in capacitance using a period measurement instead of frequency measurement.

Using this new method provides higher resolution than the frequency measurement and permits faster scanning.

THEORY OF OPERATION

The basic principle is that a relaxation oscillator will be created with the microcontroller and the sensing pad's capacitance. This oscillation should be on the order of 200 to 500 kHz (using the CSM module, no work is required but to have a sensor pad, and the oscillations will be in this range when using the high power setting; for the SR latch devices, a 100 kOhm feedback resistor will typically put the sensors in that region - Figure A-1). When a user's finger touches the sensor, it will reduce the relaxation oscillator frequency and increase the period. This increase in period will be detected.

Configuring the Hardware

The period will not be measured as a value, such as 8µsec but, instead, will be a count in Timer1 representing period through some scaling factors. This method will use Timer0 and Timer1, but now the inputs to Timer0 and Timer1 are reversed. The input of Timer1 will be $F_{OSC}/4$, or a multiple, and the input of Timer0 will be the relaxation oscillator drive signal.

Figure 1 on page 3 shows how to configure the PIC16F727 family of devices to perform this period measurement using the Cap Sense Module (CSM).

Obtaining a Reading

At the beginning of a reading, Timer1 is cleared, and Timer0 may be cleared or preloaded with a fixed value. Preloading a value, other than 0, will make the sampling time shorter. On the interrupt of Timer0, the value of Timer1 is the reading. The internal oscillator of the device will run at 4, 8, or 16 MHz, orders of magnitude faster than the relaxation oscillator. The Timer1 result is a ratio of the frequency of the internal oscillator over the frequency of the relaxation oscillator, and this is multiplied by the number of periods measured (how many times Timer0 counted – 255 periods if starting from 0), as shown in Equation 1 below:

EQUATION 1:

$$\text{reading} = (F_{OSC}/4)/(F_{RELAXOSC}) \cdot N$$

The Timer1 value is a representation of the period of the relaxation oscillator. This value will be watched for an increase, signaling touch.

SOFTWARE DECODING

The software decoding for the period measurement is identical to the frequency measurement methods, except now the reading goes up for a touch, instead of down. Previously, as frequency decreased, the same decrease was seen in the reading.

Also, the period measurement is linear only for small shifts, less than 5-10%. A percentage can still be computed from the value, and is still useful, but for large shifts, since the period is $1/f$, it increases exponentially. If you have a large shift, then the signal shift will be extremely large, allowing for plenty of shift in the data to work with.

BENEFITS AND TRADE-OFFS

Faster

The sensor can be sampled in a shorter time for an equal amount of resolution and debouncing, compared to the frequency method. The decrease in sampling time is on the order of 2-5 times. This method can work acceptably with as few as 32 periods of the relaxation oscillator (preload $TMR0=255-32$). Scanning faster can allow more time for debouncing. The alternative to scanning faster is to have the same sample time, which will increase resolution.

Higher Resolution

This method provides a higher resolution in the same amount of time, compared to the frequency method. The reason is that using frequency directly, a single bit count was a change in 1 period of the relaxation oscillator. Using $FOSC/4$, as described above, gives sampling points within a single relaxation oscillator period. The end result is that for a 5% shift, you will see 5% shift on both the frequency measurement and period measurement, but you will get more counts of resolution between 0 and 5% using the period measurement.

This increase in resolution is most beneficial when using weaker sensors, since all resolution obtainable is needed, and there is little margin. In stronger sensors, both methods work equally well.

Additional Safety Catch

The frequency method has an automatic time out if a sensor is stuck or grounded. That sensor will naturally be dead (since it is grounded), and then the other sensors will continue to operate. There is a small amount of overhead to add a check on Timer1 to overflow, in order to ensure a sensor is not dead with the period measurement. This is required because Timer0 will not increment if the sensor is grounded, and then could create a potential lockup of all keys, not just one. So, the new period method requires an additional condition to be observed.

Non-constant Sample Time

The period measurement does introduce sample times for sensors which are not constant. Since it depends on the relaxation oscillator to get the reading, as you touch the sensor, it will take longer to read the sensor. For small changes, the time is mostly linear. If a sensor's capacitance changes by 5%, that sensor will take 5% longer to sample. If the sampling time is 1 ms, it would then take about 1.05ms. This is good for yielding higher resolution, but is not desirable if you want a constant sampling time.

Code Usage

The memory and RAM usage of both period and frequency measurements are very comparable, and there is not much difference between the two methods here.

CONCLUSIONS

The new period measurement is a good method to use when weak sensors are used, such as cases with thick plastic covers. It is best in situations like that to add the extra resolution, for the same amount of time spent scanning.

This new method allows for flexibility in a trade-off between speed and resolution. If scanning speed is too slow, it can be made to work faster, and if higher resolution is required, it allows for that too. The final user's balance is more flexible in the range of speed and resolution.

Microchip also has other useful application notes about its mTouch™ Capacitive Touch Sensing Solutions. These application notes cover the basics of capacitive touch sensing, as well as different methods for tiny parts, like the PIC10F family, or large parts such as some PIC24F families.

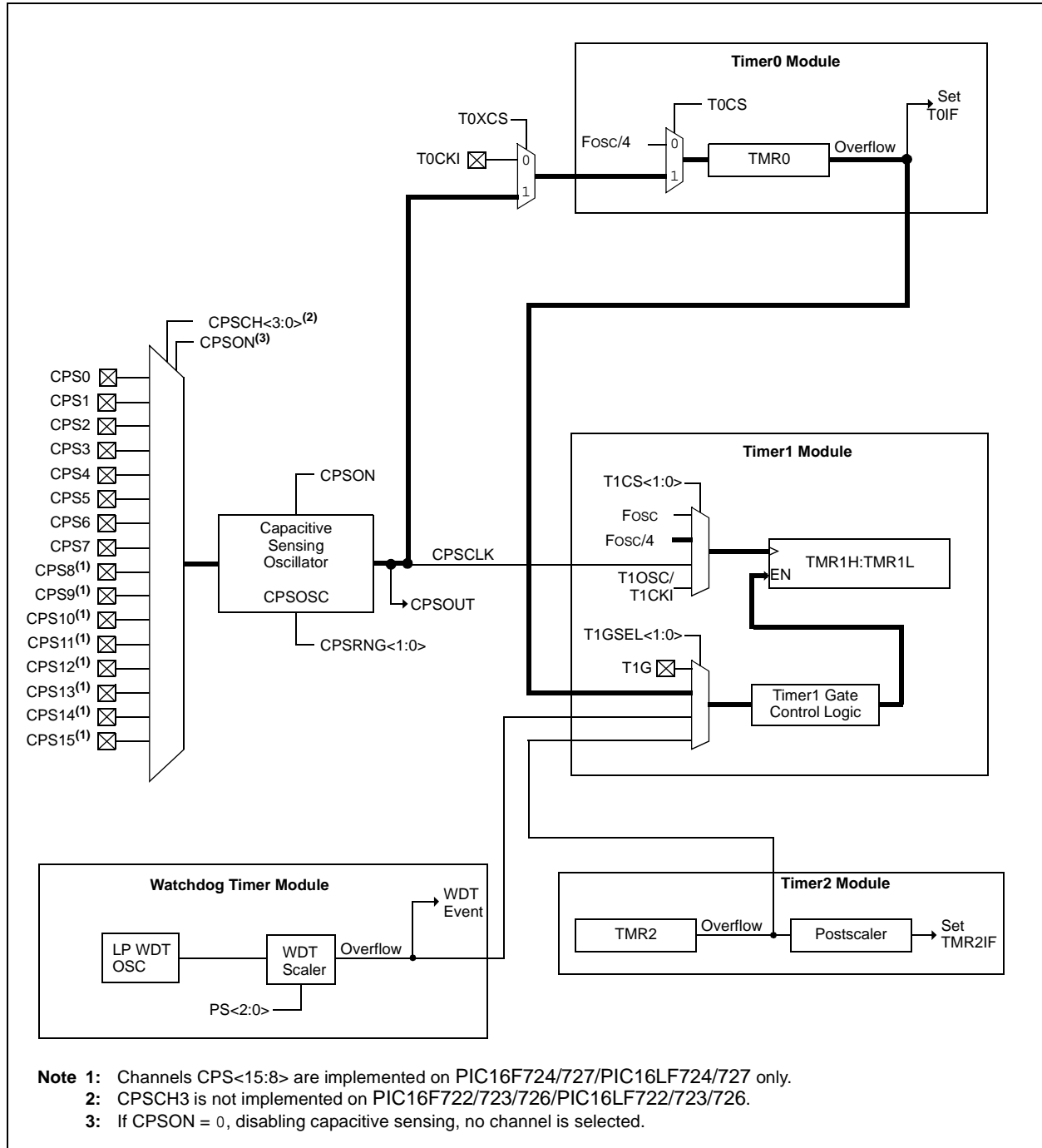
REFERENCES:

- AN1101, "Introduction to Capacitive Sensing"
- AN1102, "Layout and Physical Design Guidelines for Capacitive Sensing"
- AN1103, "Software Handling for Capacitive Sensing"
- AN1104, "Capacitive Multibutton Configurations"
- AN1171, "Using Capacitive Sensing Module with PIC16F72X"
- AN1202, "Capacitive Sensing with PIC10F"
- AN1250, "Microchip CTMU for Capacitive Touch Applications"

WEBINARS:

- Introduction to mTouch™ Capacitive Touch Sensing
- Capacitive mTouch™ Sensing Solutions: Design Guidelines.

FIGURE 1: CONFIGURING PIC16F727 FOR PERIOD MEASUREMENT



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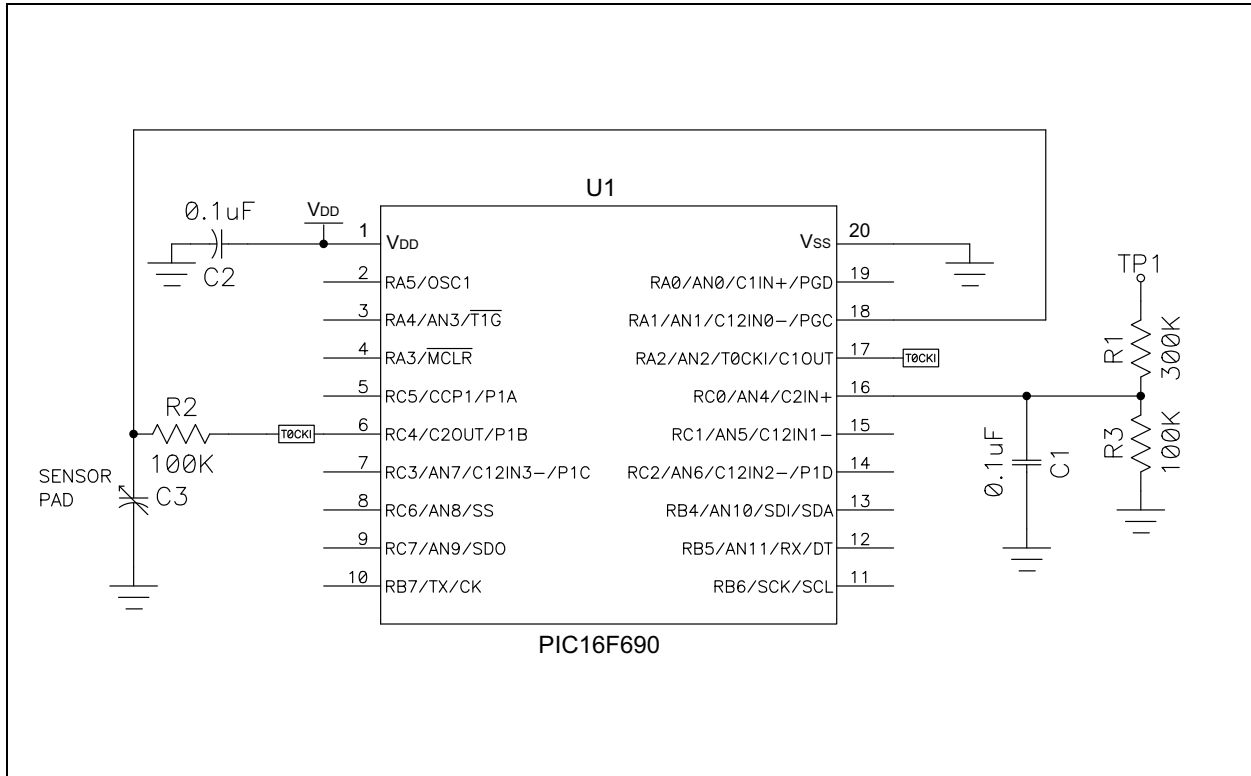
NOTES:

APPENDIX A: SCHEMATICS

The SR Latch schematic, illustrated in Figure A-1, shows how the oscillator drive signal goes into T0CKI, and how the feedback signal goes into C12IN0-.

Using a part with the CSM only requires a wire to a pad for the schematic. The setup is done internally as shown in Figure 1, which configures the CSM to send the CPSOSC (drive signal) to T0CKI, and increment Timer1 from Fosc/4.

FIGURE A-1: SR LATCH SCHEMATIC



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NOTES:

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