

A MICROMECHANICAL RESONATOR

Field of the invention

5

The invention relates to design of micromechanical resonators and, more precisely, to the design of microelectromechanical systems (MEMS) resonators. The object of the invention is to provide an improved design structure for a microelectromechanical systems (MEMS) resonator that is frequency robust to manufacturing variations and enabling reliable frequency referencing with good performance, particularly in small size solutions.

15

Background of the invention

Resonators form a key component of a timing or frequency reference. The resonators are actuated to oscillate near the natural resonant frequency. This natural resonant frequency depends on the material and shape of the resonators.

For reference applications, it is desired that the resonant frequency is precisely controlled. For typical applications, the required frequency accuracy ranges from 1 to 100 part per million (ppm). This ppm level accuracy requires extremely good manufacturing tolerances. In addition, final calibration in the form of mechanical and/or electrical adjustment is often performed.

Micromechanical resonators have been widely used as a key component in MEMS devices, such as micro-gyroscopes, microvibromotors, micro-engines and microwave systems. The resonators are actuated, e.g. electrostatically, to oscillate near the natural resonant frequency.

Furthermore, micromechanical resonators are may also be used to complement quartz technology in frequency references. However, the frequency accuracy of micromechanical resonators needs to be improved before
5 they can challenging the quartz technology.

Micromechanical resonators that are made by a combination of optical lithography and etching processes offer size and cost advantages over conventional quartz crystal
10 resonators. However, the manufacturing variations in a micromechanical process can be several percentages of the devices dimensions.

For a better understanding of the prior art relation to
15 the present invention reference will be made to the accompanying drawings, in which:

Figure 1 illustrates a basic mechanical resonator according to prior art.

Figure 2 illustrates a lumped model for the basic
20 mechanical resonator according to prior art.

Figure 1 illustrates a basic mechanical resonator according to prior art. A simple resonator consists of a spring element 1 and a rectangular mass 2. The spring
25 element 1 can for example be a mechanical cantilever spring 1 as shown in FIG. 1.

In a simple resonator of FIG. 1, the resonant frequency ω_0 is given by
30

$$\omega_0 = \sqrt{\frac{k}{m}}, \quad (1)$$

where the spring constant k is given by

$$k = Y \frac{w^3 h}{4L^3} . \quad (2)$$

Figure 2 illustrates a lumped model for the basic mechanical resonator according to prior art. Here Y is the Young's modulus for the material, w is the width of the spring element, h is the height of the spring element, and L is the spring element length. The spring element width w is typically small and due to cubic dependency, the resonant frequency ω_0 is very sensitive to the variations in spring element width w .

The first-order change of the resonant frequency ω_0 with respect to spring element width w is

$$\frac{\Delta\omega_0}{\omega_0} = \frac{3}{2} \frac{\Delta w}{w} , \quad (3)$$

where $\partial\omega_0$ is the infinitesimal frequency change due to the infinitesimal spring element width change ∂w . One of the most significant problems in the design of micromechanical resonators is the variation of the resonant frequency, which is caused by poor dimensional precision in the structures. In resonators manufactured using the means of micromechanics, there may be quite substantial dimensional tolerance errors.

For example, following from the above equation (Equation 3), if the spring element width varies by 4%, the resonant frequency varies by 6% or 60,000 ppm. To reduce this variation, it is desired that the resonant frequency is relatively unaffected by the manufacturing variations.

Patent document US2005073078 discloses a resonator that has a spring mechanism connected between an anchor and an

effective mechanical mass. Patent document US2007182291 discloses a thin film tuning fork type inflection resonator. However, at their closest said patent documents describe only techniques according to the pre-amble part
5 of an independent claim.

Thus, the object of the invention is to provide a structure of a micromechanical resonator which has an
10 improved frequency accuracy in comparison to the prior art solutions. The present invention meets this need.

Summary of the invention

15 The objective of the invention is to provide such an improved design structure for a microelectromechanical systems (MEMS) resonator, which is frequency robust to manufacturing variations and which enables reliable frequency referencing with good performance, particularly
20 in small size solutions.

According to a first aspect of the invention, there is provided a micromechanical resonator having a movable mass structure and a spring structure; said movable mass
25 structure consisting of at least two electrode fingers that are connected together, and said spring structure consisting of at least one spring element that is anchored from one end and connected to the mass on the other end, in which the width of the spring elements is greater than
30 the width of the electrode fingers, said widths specifically dimensioned so that the sensitivity of the resonant frequency change with respect to dimensional manufacturing variations $d(\Delta\omega_0/\omega_0)/d\delta$ approaches zero.

35 Preferably, the micromechanical resonator has the width of the spring elements 2 to 5 times the width of the

4a

electrode fingers. Alternatively, the micromechanical resonator has the width of the spring elements approximately 3 times the width of the electrode fingers.

- 5 Preferably, the resonant frequencies of said electrode fingers are 2 to 5 times higher than the resonant frequency for the resonator. Further preferably, in dimensioning said widths, said widths are dimensioned so that the slope of the resonant frequency change with

10

respect to dimensional manufacturing variation change approaches zero at two or more locations. Further preferably, said spring structure consists of two spring elements that are anchored together to form a tuning fork
5 structure.

Further preferably, in dimensioning said widths, the resonance frequency $\omega_f = 0.8 \sqrt{\frac{Y}{\rho}} \frac{w_f}{L^2}$ of the electrode fingers is taken into account. Further preferably, in dimensioning
10 said widths, the effect of bending of the electrode fingers is taken into account.

Preferably, the length of the electrode fingers is also dimensioned so that electrode finger resonant frequency
15 affects the resonator resonant frequency so that a localized maximum of the resonator resonant frequency change with respect to dimensional manufacturing variation change is generated. Preferably, the micromechanical resonator has the length of the electrode fingers 1/6 to
20 1/2 times the length of the spring elements.

Preferably, the micromechanical resonator additionally has means for actuating the resonator electrostatically. Preferably, the micromechanical resonator has the width of
25 the electrode gap from 500 nm to 5 μ m.

Brief description of the drawings

For a better understanding of the present invention and in order to show how the same may be carried into effect
30 reference will now be made to the accompanying drawings, in which:

Figure 1 illustrates a basic mechanical resonator according to prior art.

Figure 2 illustrates a lumped model for the basic mechanical resonator according to prior art.

Figure 3 illustrates the dimension changes of a basic mechanical resonator due to lithography or etch variations
5 according to the present invention.

Figure 4 illustrates a micromechanical resonator structure according to the present invention.

Figure 5 illustrates the frequency change of the resonant frequency of the micromechanical resonator
10 structure according to the present invention as function of the dimension change.

Figure 6 illustrates a lumped model for a micromechanical resonator structure according to the present invention.

15 Figure 7 illustrates the frequency change of the resonant frequency of the micromechanical resonator structure having spring element width three times the electrode finger width and elastic electrode fingers according to the present invention as function of the
20 dimension change.

Figure 8 illustrates an electrostatic excitation of a micromechanical resonator structure according to the present invention.

Figure 9 illustrates the relative frequency change of
25 the resonant frequency of the micromechanical resonator structure having spring element width three times the electrode finger width and including the electrical spring effect according to the present invention as function of the dimension change.

30 Figure 10 illustrates the frequency change of the resonant frequency of the micromechanical resonator structure having spring element width three times the electrode finger width, having elastic electrode fingers, and including the electrical spring effect according to
35 the present invention as function of the dimension change.

Figure 11 illustrates a micromechanical resonator structure having spring element width three times the

electrode finger width, having elastic electrode fingers, and including the electrical spring effect according to the present invention as function of the dimension change.

Figure 12 illustrates another embodiment of a
5 micromechanical resonator structure having spring element width three times the electrode finger width, having elastic electrode fingers, and including the electrical spring effect according to the present invention as function of the dimension change.

10

The Figures 1 and 2 referring to the prior art have been discussed earlier. In the following, reference is made to the Figures 3-12.

15 Detailed description of certain embodiments

The solution according to the present invention presents a new structure of a micromechanical resonator which has an improved frequency accuracy in comparison to the prior art
20 solutions.

Figure 3 illustrates the dimension changes of a basic mechanical resonator due to lithography or etch variations according to the present invention. The key in reducing
25 the effect of manufacturing variations is to note that in a typical micromanufacturing process, many dimensions change by an almost equal amount.

For example, in the case of the simple resonator of FIGS 1
30 and 2, all the dimensions may change by an equal absolute amount δ due to lithography or etch variations as illustrated in FIG. 3. In the new structure of a micromechanical resonator according to the present invention the resonator is designed so that it is
35 frequency insensitive to uniform dimensions changes.

Figure 4 illustrates a micromechanical resonator structure according to the present invention. The micromechanical resonator structure according to the present invention is frequency insensitive to the manufacturing variations.

5

The micromechanical resonator structure according to the present invention comprises a spring structure 3 and a movable mass structure 4. The spring structure 3 according to the present invention comprises at least one spring
 10 element 3. The movable mass structure 4 according to the present invention comprises several electrode fingers 5-9 with width w_f . The total mass of the fingers is:

$$m = Nw_fhL_f\rho, \quad (4)$$

15

where N is the number of the electrode fingers 5-9, w_f is the electrode finger width, h is the height, L_f is the electrode finger length, and ρ is the density.

20 The first order change of resonant frequency ω_0 with respect to dimension variations is:

$$\frac{\Delta\omega_0}{\omega_0} = \frac{3}{2} \frac{\Delta w}{w} - \frac{1}{2} \frac{\Delta w_f}{w_f} = 3 \frac{\delta}{w} - \frac{\delta}{w_f}. \quad (5)$$

25 In this calculation of the frequency change of the micromechanical resonator structure according to the present invention we have assumed that the spring and electrode finger width change from both sides by an equal amount of dimension change δ and that lengths L and L_f are
 30 long compared to the dimension change δ so that the changes due to length variations can be ignored.

We may especially choose the width of the spring elements 3 greater than the width of the electrode fingers 5-9 and

specifically dimension said widths so that to the first order the sensitivity of the resonant frequency with respect to dimensional manufacturing variations approaches zero.

5

By choosing spring element width w so that it is 2 to 5 times, or alternatively approximately three times the electrode finger width w_f ($w=3w_f$), in the calculation of the sensitivity of the micromechanical resonator structure

10 according to the present invention we get $\frac{\Delta\omega_0}{\omega_0}=0$

(Equation 5) and the resonant frequency is insensitive to manufacturing variations to the first order.

In the calculation of the mass of the micromechanical resonator structure according to the present invention we have used the above equation (Equation 4), which is a lumped mass approximation and does not account for the tip of the electrode fingers 5-9 moving more than the base of the spring element 3. Also, the anchoring of the electrode fingers 5-9 has been ignored in the above equation for mass (Equation 4) and accounts only for the mass of the electrode fingers 5-9.

Taking this into account the optimal value for the electrode finger width may therefore vary but it is approximately given by $w=3w_f$. By substituting $w \rightarrow w+2\delta$ and $w_f \rightarrow w_f+2\delta$ to above equations (Equations 1, 2 and 4), the sensitivity in the change of resonant frequency due to manufacturing variations can be analyzed.

30

Figure 5 illustrates the frequency change of the resonant frequency of the micromechanical resonator structure according to the present invention as function of the dimension change. The presented graph 10 shows the

frequency change $\frac{\Delta\omega_0}{\omega_0}$ of the resonant frequency ω_0 as function of the dimension change δ . In the Figure 5, $w = 3$ is the width of the spring and $W = 1$ is the width of the mass fingers.

5

From the presented graph 10 it is seen that the slope $\frac{d(\Delta\omega_0/\omega_0)}{d\delta}$ is zero at $\delta = 0$ and the manufacturing variations are compensated to the first order. The slope $\frac{d(\Delta\omega_0/\omega_0)}{d\delta}$ is defined as the frequency sensitivity to the manufacturing dimensional variations. By properly dimensioning the resonator, the frequency sensitivity to the manufacturing dimensional variations $\frac{d(\Delta\omega_0/\omega_0)}{d\delta}$ approaches zero and the manufacturing variations are compensated to the first order.

15

In dimensioning said widths, one may also dimension said widths so that additional zero slope points ($\frac{d(\Delta\omega_0/\omega_0)}{d\delta} = 0$) are generated and the sensitivity of resonant frequency with respect to dimensional manufacturing variations approaches zero.

20

Additional compensation is possible by noting that the electrode fingers are not entirely rigid but have a resonance frequency given by:

25

$$\omega_f = 0.8 \sqrt{\frac{Y}{\rho}} \frac{w_f}{L^2} . \quad (6)$$

The electrode fingers typically have a resonant frequency higher than the resonant frequency for the combined resonator. However, even at frequencies lower than the

30

electrode finger resonant frequency, the electrode fingers bend a little. Each electrode finger can be represented with a mass and a spring. In addition, the anchor point has mass.

5

Figure 6 illustrates a lumped model for a micromechanical resonator structure according to the present invention. The lumped model for a micromechanical resonator structure according to the present invention as presented in FIG. 5
 10 can be used for understanding the effect of bending of the electrode fingers.

In the lumped model of FIG. 6 the spring 11 models the spring constant k of the spring element as before and the
 15 electrode fingers are modeled with two masses 12, 13 and a spring 14, where $m_f = m/2$ and mass spring constant is k_f . As the electrode finger is not entirely rigid, the two masses 12, 13 will have slightly different displacements. Lumped model for the resonator with parallel electrode fingers
 20 shown as one mass 13 and spring 14. For simplicity, the two masses 12, 13 are presented in FIG. 6 as equal but this is for illustration purposes only. For actual device, the lumped masses 12, 13 may not be equal depending on the dimensions.

25

The resonant frequency ω for the lumped model in FIG. 6 is obtained as:

$$\omega^2 = \frac{k + 2k_f - \sqrt{k^2 + 4k_f^2}}{m}. \quad (7)$$

30

By noting that $k/k_f < 1$, a series expansion of the above equation (Equation 7) can be obtained as:

$$\omega^2 \approx \omega_0^2 - \frac{1}{4} \omega_0^2 \frac{k}{k_f} = \omega_0^2 \left(1 - \frac{1}{4} \frac{k}{k_f} \right), \quad (8)$$

where $\omega_0 = \sqrt{k/m}$. As the above equation (Equation 8) shows, accounting for the electrode finger compliance lowers the resonant frequency.

Moreover, as the earlier presented equation for the spring constant k (Equation 2) shows, the spring constants are proportional to the cube of spring element widths. Therefore, the above equation (Equation 8) can be written as:

$$\omega^2 \approx \omega_0^2 \left(1 - \frac{1}{4} \frac{L_f^3}{L^3} \frac{w^3}{w_f^3} \right) = \omega_0^2 \left(1 - a \frac{w^3}{w_f^3} \right), \quad (9)$$

where w is the width of the spring element, w_f is the width of the electrode finger and a is a parameter depending on the spring element and electrode finger lengths.

As $w_f < w$, the above equation (Equation 9) shows that due to distributed compliance of the electrode fingers, reducing the electrode finger width and spring element width by an equal amount will change the value of the correction term $\left(1 - a \frac{w^3}{w_f^3} \right)$ in the above equation (Equation 9). This gives an additional degree of freedom to reduce the frequency sensitivity to manufacturing variations.

Figure 7 illustrates the frequency change of the resonant frequency of the micromechanical resonator structure having spring element width three times the electrode finger width ($w = 3w_f$) and elastic electrode fingers

according to the present invention as function of the dimension change.

The presented graphs 15-18 show the frequency change $\frac{\Delta\omega_0}{\omega_0}$ of the resonant frequency ω_0 as function of the dimension change δ .

From the presented graphs 15-18 it is seen that in addition to the resonant frequency change $\frac{\Delta\omega_0}{\omega_0}$ having the local minima A at $\delta = 0$, there also is local maxima B, which are also observed for small values of the parameter a . Thus, there are two points where the slope $\frac{d(\Delta\omega_0/\omega_0)}{d\delta}$ is zero and the manufacturing variations are compensated to the second order. Increasing the value of the parameter a will lower the local maximum and with a sufficiently large value for the parameter a no local dependency frequency change on dimension change will become monotonic. This gives an additional degree of freedom to reduce the frequency sensitivity to manufacturing variations as illustrated in FIG. 7.

The proper dimensioning of the spring element and electrode finger widths is used to compensate for the manufacturing variation to the first order leading to local minima in resonant frequency (point A). By choosing the electrode finger length so that electrode finger resonant frequency affects the resonator resonant frequency, a localized maximum can be generated (point B). These two degrees of freedom (dimensioning of the widths and lengths) can be used to design a resonator that is insensitive to manufacturing variations over large dimensional change δ as illustrated in FIG. 7.

Figure 8 illustrates an electrostatic excitation of a micromechanical resonator structure according to the present invention. The multiple electrode fingers of the micromechanical resonator structure according to the present invention can be used for electrostatic excitation of the resonator. A fixed counter electrode is a distance d from the moving resonator electrode. The resonator electrode and fixed electrode form a capacitor. When a voltage V is applied over the resonator and fixed electrode, a force

$$F = \frac{1}{2} \frac{\partial C(x)}{\partial x} V^2, \quad (10)$$

will affect the resonator. As the capacitance C is proportional to the total area, a large number of electrode fingers can be used for effective actuation of the resonator.

Furthermore, the electrostatic force given by the above equation (Equation 10) can be used to tune the resonant frequency. This can be used to electronically calibrate out any remaining manufacturing variations and temperature frequency dependency of the resonator.

The effective spring force from (10) is:

$$k_e = -\frac{b}{d^3} V^2, \quad (11)$$

where b is a constant that depends on the electrode area, the electrode position, and the permittivity, d is the electrode gap, and V is the bias voltage. Due to manufacturing variations, the actual electrode gap is

$$d = d_0 - \delta, \quad (12)$$

where d_0 is the ideal electrode spacing and δ is the dimension change of the electrode. If the size of the electrode increases, the gap between the electrodes decreases. As noted from the two previous equations:

$$k_e = -\frac{b}{(d_0 - \delta)^3} V^2, \quad (13)$$

the electrical spring can further compensate the manufacturing variations. The resonant frequency modified by the electrical spring force is given by

$$\begin{aligned} \omega_0 &= \sqrt{\frac{k + k_e}{m}} = \sqrt{\frac{k}{m} \left(1 + \frac{k_e}{k}\right)} \Rightarrow \\ \omega_0 &= \omega_0 \sqrt{\left(1 + \frac{k_e}{k}\right)} = \omega_0 \sqrt{\frac{(w + \delta)^3}{(w_f + \delta)} \left(1 - c \frac{(w_f + \delta)^3}{(d_0 - \delta)^3}\right)}, \quad (14) \end{aligned}$$

15

where c is dimension dependent constant.

Figure 9 illustrates the relative frequency change of the resonant frequency of the micromechanical resonator structure having spring element width three times the electrode finger width and including the electrical spring effect according to the present invention as function of the dimension change.

25 The graph in FIG. 9 shows the relative frequency change

$\frac{\Delta\omega_0}{\omega_0}$ of the resonant frequency ω_0 as function of the

dimension change δ . For positive values of dimension change, the electrical spring will reduce frequency change.

30

From the graph it is seen how the electrical spring effect can be used to further minimize the frequency change due to dimension change. If further reduction in variation is needed, the final trimming of the device can be

5 accomplished by adjusting the bias voltage V to adjust the electrical spring or by physical trimming such as laser trimming.

10 The solution according to the present invention presents a new structure of a micromechanical resonator which has an improved frequency accuracy in comparison to the prior art solutions. The optimal device dimensions are obtained by combining the demonstrated effects.

15 In the solution according to the present invention the spring element width w and the electrode finger width w_f are chosen so that spring element width w is approximately three times the electrode finger width w_f ($w=3w_f$). The relationship is not exact as the electrode finger support
20 has not been considered and the other two compensation methods can be used to tailor dependency of the device resonant frequency on dimension changes. The optimal range for the spring element width can vary from the spring element width w being approximately two to five times the
25 electrode finger width w_f ($w=2w_f$ to $w=5w_f$).

In the solution according to the present invention the electrode finger length L_f is chosen to be sufficiently long so that the distributed elasticity of the electrode
30 finger affects the resonant frequency. The optimal range for the electrode finger length may vary from $L_f=L/6$ to $L_f=L/2$.

In the solution according to the present invention the
35 electrode gap d is chosen to be sufficiently small to

affect the resonant frequency. The optimum gap ranges from 500 nm to 5 μ m.

Figure 10 illustrates the frequency change of the resonant frequency of the micromechanical resonator structure having spring element width three times the electrode finger width, having elastic electrode fingers, and including the electrical spring effect according to the present invention as function of the dimension change.

The presented graphs 19-22 show the change in the resonant frequency $\frac{\Delta\omega_0}{\omega_0}$ of the resonant frequency ω_0 as function of the dimension change δ . The presented graphs 19-22 show the effect of combining all the previously mentioned three approaches and shows how the sensitivity to dimensional change can be minimized for a wide range of variations. Combination of the three mentioned compensation methods is used to obtain minimal frequency change. In the curves, the resonator dimensions are changed and the gap is varied.

Figure 11 illustrates a micromechanical resonator structure having spring element width three times the electrode finger width, having elastic electrode fingers, and including the electrical spring effect according to the present invention as function of the dimension change.

The resonator is made of single crystal silicon and has two spring elements 23, 24 anchored at the same location.

This tuning fork structure minimizes the spring element anchor movement thus minimizing the anchor losses. Both spring elements 23, 24 have a mass made of multiple electrode fingers 25, 26. The resonator has two spring elements anchored at the same location the mass is formed by multiple electrode fingers 25, 26. The vibration mode

minimizes the anchor losses as the motion of the two spring elements 23, 24 cancel. The resonator target resonance frequency is 32,768 Hz and the dimensions are given in Table 1 below.

5

Parameter	Dimension [μm]
Spring element length	265
Spring element width	12.6
Electrode finger length	200
Electrode finger width	3
No. of electrode fingers	14
Electrode gap	3

Table 1.

10 Figure 12 illustrates another embodiment of a micromechanical resonator structure having spring element width three times the electrode finger width, having elastic electrode fingers, and including the electrical spring effect according to the present invention as
 15 function of the dimension change.

In FIG. 12 the mass is made of multiple electrode fingers 31-34 and the spring element width w is approximately three times the electrode finger width w_f ($w_f = w/3$). The
 20 device is anchored with multiple spring elements 27-30 i.e. guided beams 27-30 to restrain the mass movement in one direction only. As the spring elements 27-30 cannot rotate freely, the guided beam spring elements 27-30 are four times stiffer than the simple cantilever springs with
 25 equal length. Conversely, to obtain the same spring

constant, the guided beams 27-30 should be longer than a simple spring. In FIG. 12 the guided beam spring elements 27-30 are thicker than the electrode fingers 31-34 to compensate for the dimensional changes. Also, the resonant
5 frequency of electrode fingers 31-34 is slightly higher than the resonant frequency for the whole resonator.

The micromechanical resonator structure according to the present invention is insensitive to systematic
10 manufacturing variations.

Claims

1. A micromechanical resonator having a movable mass structure (4) and a spring structure (3), (23-24), (27-30); said movable mass structure (4) consisting of at least two electrode fingers (5-9), (25-26), (31-34) that are connected together, and said spring structure (3), (23-24), (27-30) consisting of at least one spring element (3), (23-24), (27-30) that is anchored from one end and connected to the mass on the other end, characterized in that the width of the spring elements (3), (23-24), (27-30) is greater than the width of the electrode fingers (5-9), (25-26), (31-34), said widths specifically dimensioned so that the sensitivity of the resonant frequency change with respect to dimensional manufacturing variations $d(\Delta\omega_0/\omega_0)/d\delta$ approaches zero and the fingers act as mass and actuating electrodes.

2. A micromechanical resonator according to Claim 1, characterized in that the micromechanical resonator has the width of the spring elements (3), (23-24), (27-30) 2 to 5 times the width of the electrode fingers (5-9), (25-26), (31-34).

3. A micromechanical resonator according to Claim 1, characterized in that the micromechanical resonator has the width of the spring elements (3), (23-24), (27-30) approximately 3 times the width of the electrode fingers (5-9), (25-26), (31-34).

4. A micromechanical resonator according to any one of the claims 1-3, characterized in the resonant frequencies of said electrode fingers (5-9), (25-26), (31-34) are 2 to 5 times higher than the resonant frequency for the resonator.

5. A micromechanical resonator according to any one of the claims 1-4, **characterized** in that in dimensioning said widths, said widths are dimensioned so that the slope of the resonant frequency change with respect to dimensional manufacturing variation change approaches zero at two or more locations.

6. A micromechanical resonator according to any one of the claims 1-5, **characterized** in that said spring structure (23-24) consists of two spring elements (23-24) that are anchored together to form a tuning fork structure.

7. A micromechanical resonator according to any one of the claims 1-6, **characterized** in that in dimensioning said widths, the resonance frequency $\omega_f = 0.8 \sqrt{\frac{Y}{\rho}} \frac{w_f}{L^2}$ of the electrode fingers (5-9), (25-26), (31-34) is taken into account.

8. A micromechanical resonator according to any one of the claims 1-7, **characterized** in that in dimensioning said widths, the effect of bending of the electrode fingers (5-9), (25-26), (31-34) is taken into account.

9. A micromechanical resonator according to any one of the claims 1-8, **characterized** in that the length of the electrode fingers is also dimensioned so that electrode finger resonant frequency affects the resonator resonant frequency so that a localized maximum of the resonator resonant frequency change with respect to dimensional manufacturing variation change is generated.

10. A micromechanical resonator according to Claim 9, **characterized** in that the micromechanical resonator has the length of the electrode fingers (5-9), (25-26), (31-

34) $1/6$ to $1/2$ times the length of the spring elements
(3), (23-24), (27-30).

11. A micromechanical resonator according to any one of
5 the claims 1-10, **characterized** in that the micromechanical
resonator additionally has means for actuating the
resonator electrostatically.

12. A micromechanical resonator according to any one of
10 the claims 1-11, **characterized** in that the micromechanical
resonator has the width of the electrode gap from 500 nm to
 $5\text{ }\mu\text{m}$.