

# 855 Robotic Titrosampler



## Manual

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Metrohm AG  
CH-9100 Herisau  
Switzerland  
Phone +41 71 353 85 85  
Fax +41 71 353 89 01  
[info@metrohm.com](mailto:info@metrohm.com)  
[www.metrohm.com](http://www.metrohm.com)

# **855 Robotic Titrosampler**

## **Manual**

Technical Communication  
Metrohm AG  
CH-9100 Herisau  
[techcom@metrohm.com](mailto:techcom@metrohm.com)

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# Table of contents

|          |   |           |
|----------|---|-----------|
| <b>1</b> | <b>Introduction</b>                                       | <b>1</b>  |
| 1.1      | The 855 Robotic Titrosampler in the Titrando system ..... | 1         |
| 1.2      | Instrument description .....                              | 2         |
| 1.2.1    | Model versions .....                                      | 3         |
| 1.2.2    | Instrument components .....                               | 4         |
| 1.2.3    | Intended use .....  | 4         |
| 1.3      | About the documentation .....                             | 5         |
| 1.3.1    | Symbols and conventions .....                             | 5         |
| 1.4      | Safety instructions .....                                 | 6         |
| 1.4.1    | General notes on safety .....                             | 6         |
| 1.4.2    | Electrical safety .....                                   | 6         |
| 1.4.3    | Tubing and capillary connections .....                    | 7         |
| 1.4.4    | Personnel safety .....                                    | 7         |
| 1.4.5    | Flammable solvents and chemicals .....                    | 9         |
| 1.4.6    | Recycling and disposal .....                              | 9         |
| <b>2</b> | <b>Overview of the instrument</b>                         | <b>10</b> |
| 2.1      | Front and rear .....                                      | 10        |
| 2.2      | Back panel .....  | 12        |
| 2.3      | Sensor connectors .....                                   | 12        |
| 2.4      | Sample racks .....  | 13        |
| <b>3</b> | <b>Installation</b>                                       | <b>15</b> |
| 3.1      | Setting up the instrument .....                           | 15        |
| 3.1.1    | Packaging .....   | 15        |
| 3.1.2    | Checks .....  | 15        |
| 3.1.3    | Location .....  | 15        |
| 3.2      | Preparing the Sample Processor .....                      | 15        |
| 3.2.1    | Connecting the instrument to the power grid .....         | 15        |
| 3.3      | Connecting a computer .....                               | 16        |
| 3.4      | Connecting the Swing Head .....                           | 18        |
| 3.5      | Configuring the robotic arm .....                         | 19        |
| 3.6      | Mounting the robotic arm .....                            | 21        |
| 3.7      | Robotic arms with beaker sensor .....                     | 23        |
| 3.8      | Installing the rinsing and aspiration equipment .....     | 24        |
| 3.9      | Placing tubing and cables in the guide chain .....        | 27        |
| 3.10     | Equipping the titration head .....                        | 28        |



|             |   |           |
|-------------|---|-----------|
| <b>3.11</b> | <b>Connecting the tower stirrer .....</b>     | <b>31</b> |
| <b>3.12</b> | <b>Connecting an external pump .....</b>      | <b>32</b> |
| <b>3.13</b> | <b>Connecting MSB devices .....</b>           | <b>33</b> |
| 3.13.1      | Connecting a dosing device .....              | 34        |
| 3.13.2      | Connecting a stirrer or titration stand ..... | 35        |
| 3.13.3      | Connecting a Remote Box .....                 | 36        |
| <b>3.14</b> | <b>Connecting USB devices .....</b>           | <b>37</b> |
| 3.14.1      | Connecting a barcode reader .....             | 37        |
| <b>3.15</b> | <b>Mounting the base plate .....</b>          | <b>39</b> |
| <b>3.16</b> | <b>Mounting the drip pan .....</b>            | <b>40</b> |
| <b>3.17</b> | <b>Attaching a sample rack .....</b>          | <b>41</b> |
| <b>3.18</b> | <b>Mounting the safety shield .....</b>       | <b>42</b> |
| <b>4</b>    | <b>Operation and maintenance</b>              | <b>44</b> |
| <b>4.1</b>  | <b>General notes .....</b>                    | <b>44</b> |
| <b>4.2</b>  | <b>Care .....</b>                             | <b>44</b> |
| <b>5</b>    | <b>Troubleshooting</b>                        | <b>45</b> |
| <b>5.1</b>  | <b>Sample Processor .....</b>                 | <b>45</b> |
| <b>5.2</b>  | <b>Robotic arm .....</b>                      | <b>45</b> |
| <b>5.3</b>  | <b>Pump .....</b>                             | <b>46</b> |
| <b>6</b>    | <b>Appendix</b>                               | <b>47</b> |
| <b>6.1</b>  | <b>Beaker sensor .....</b>                    | <b>47</b> |
| <b>6.2</b>  | <b>Rinsing nozzles .....</b>                  | <b>47</b> |
| <b>6.3</b>  | <b>Remote interface .....</b>                 | <b>48</b> |
| 6.3.1       | Pin assignment of the remote interfaces ..... | 49        |
| <b>6.4</b>  | <b>Stirring rate .....</b>                    | <b>50</b> |
| <b>6.5</b>  | <b>Robotic arms .....</b>                     | <b>51</b> |
| 6.5.1       | Robotic arms for titration .....              | 51        |
| 6.5.2       | Robotic arms for sample preparation .....     | 53        |
| 6.5.3       | Robotic arms for special applications .....   | 54        |
| <b>7</b>    | <b>Technical specifications</b>               | <b>55</b> |
| <b>7.1</b>  | <b>Measuring interface .....</b>              | <b>55</b> |
| 7.1.1       | Potentiometry .....                           | 55        |
| 7.1.2       | Polarizer .....                               | 55        |
| 7.1.3       | Temperature .....                             | 56        |
| <b>7.2</b>  | <b>Lift and turntable .....</b>               | <b>56</b> |
| <b>7.3</b>  | <b>Membrane pump(s) with valve .....</b>      | <b>57</b> |



|          |  |           |
|----------|--|-----------|
| 7.4      | <b>786 Swing Head .....</b>            | <b>57</b> |
| 7.5      | <b>Interfaces and connectors .....</b> | <b>57</b> |
| 7.6      | <b>Power connection .....</b>          | <b>58</b> |
| 7.7      | <b>Ambient temperature .....</b>       | <b>58</b> |
| 7.8      | <b>Reference conditions .....</b>      | <b>58</b> |
| 7.9      | <b>Dimensions .....</b>                | <b>58</b> |
| <b>8</b> | <b>Accessories</b>                     | <b>59</b> |
|          | <b>Index</b>                           | <b>60</b> |



## Table of figures

|           |   |    |
|-----------|---|----|
| Figure 1  | The Titrando system .....                                   | 1  |
| Figure 2  | Front 855 Robotic Titrosampler .....                        | 10 |
| Figure 3  | Rear 855 Robotic Titrosampler .....                         | 11 |
| Figure 4  | Connector strip .....                                       | 12 |
| Figure 5  | Sensor connectors .....                                     | 13 |
| Figure 6  | Sample rack 6.2041.840 .....                                | 13 |
| Figure 7  | Connecting the computer .....                               | 17 |
| Figure 8  | Connecting the Swing Head .....                             | 18 |
| Figure 9  | Robotic arms - standard model versions: .....               | 19 |
| Figure 10 | Configuration data of the robotic arms .....                | 20 |
| Figure 11 | Limitation screw on the robotic arm .....                   | 21 |
| Figure 12 | Mounting the robotic arm .....                              | 22 |
| Figure 13 | Connecting a beaker sensor (for example 6.1462.150) .....   | 23 |
| Figure 14 | Mounting the rinsing and aspiration tubings .....           | 24 |
| Figure 15 | Installing the rinsing tubings and the aspiration tip ..... | 29 |
| Figure 16 | Installing stirrer and electrode .....                      | 30 |
| Figure 17 | Rod stirrer 802 Stirrer .....                               | 31 |
| Figure 18 | Magnetic stirrer 741 Stirrer .....                          | 31 |
| Figure 19 | Connecting the tower stirrer .....                          | 31 |
| Figure 20 | Connecting a pump .....                                     | 32 |
| Figure 21 | MSB connections .....                                       | 33 |
| Figure 22 | Connecting a dosing device .....                            | 35 |
| Figure 23 | Connecting an MSB stirrer .....                             | 35 |
| Figure 24 | Connecting the rod stirrer to the titration stand .....     | 36 |
| Figure 25 | Connecting the Remote Box .....                             | 37 |
| Figure 26 | USB connectors .....  | 38 |
| Figure 27 | Mounting the base plate .....                               | 39 |
| Figure 28 | Installing the drip pan .....                               | 40 |
| Figure 29 | Attaching rack .....  | 41 |
| Figure 30 | Mounting the safety shield .....                            | 42 |
| Figure 31 | Beaker sensor on the tower .....                            | 47 |
| Figure 32 | Spray nozzles - Mode of operation .....                     | 48 |
| Figure 33 | Connectors of the Remote Box .....                          | 48 |
| Figure 34 | Pin assignment of remote socket and remote plug .....       | 49 |
| Figure 35 | Rotational speed depending on the stirring rate .....       | 50 |

# 1 Introduction

## 1.1 The 855 Robotic Titrosampler in the Titrando system

The 855 Robotic Titrosampler is a component of the modular Titrando system. Operation is carried out either by a Touch Control with a touch-sensitive screen ("stand-alone titrator") or by a computer with a corresponding software.

A Titrando system can contain numerous, various kinds of instruments. The following figure provides an overview of the peripheral devices you can connect to the 855 Robotic Titrosampler.

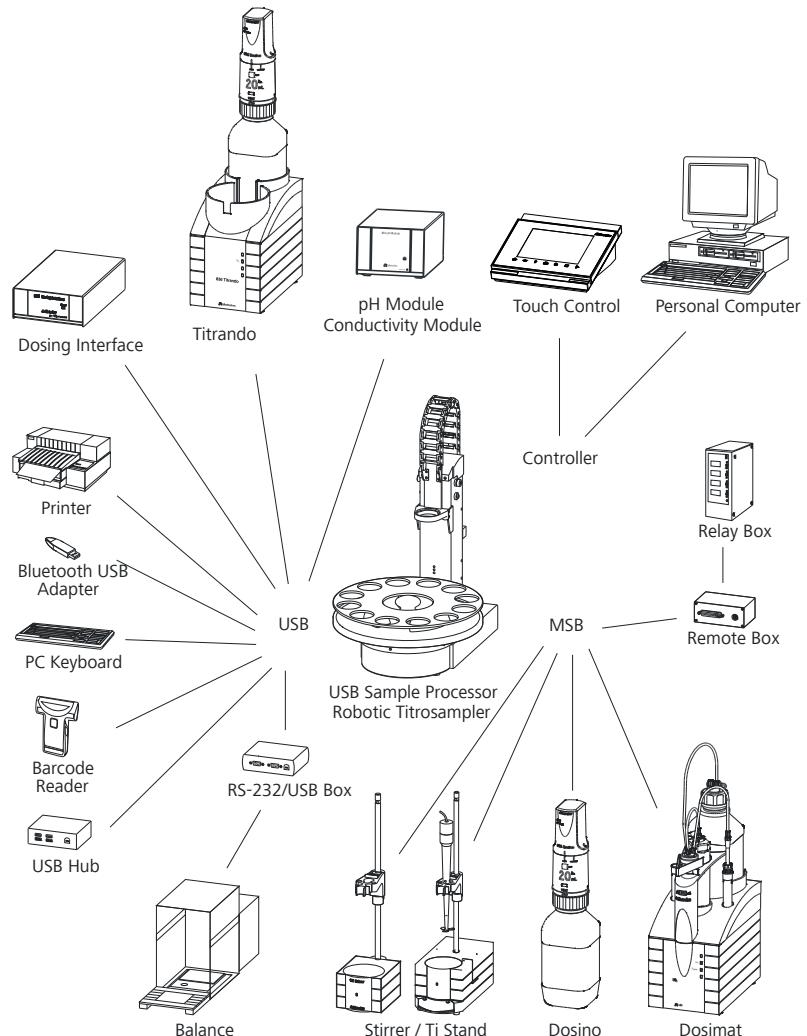


Figure 1 The Titrando system



Up to three control instruments (Titrando, Dosing Interface, USB Sample Processor, etc.) can be controlled via USB connection during operation with the 900 Touch Control. If the **tiamo** software is used, then there is no limit to the number of control instruments that can be used to extend the system.

Updating the device software is described in the manual for the Touch Control or in the online help for the **tiamo** software.

## 1.2 Instrument description

The 855 Robotic Titrosampler is a combined analyzer, unifying the functionality of a titrator and a sample changer. It can be seamlessly incorporated as a system component and control instrument into a Metrohm Titrando system.

The 855 Robotic Titrosampler is a versatile instrument. It has been designed exclusively for usage in factories, as long as ambient conditions (*see chapter 7.7, page 58*) are fulfilled, and laboratories and thereby covers a wide range of applications.

Thanks to the integration of high-performance USB interfaces, it can be incorporated seamlessly into a Metrohm Titrando system. The versatile communications options of the Titrando system (Remote Box, LIMS link, etc.) can thus all be used. Thanks to these abilities, a 855 Robotic Titrosampler is predetermined for all kind of automation tasks in a modern laboratory, especially for highly integrated laboratory data systems.

The user interface of the Touch Control or the **tiamo** software guarantees comfortable operation and programming of the 855 Robotic Titrosampler. The comprehensive range of commands and the various configuration possibilities can comfortably and efficiently be used this way. The integration into the Titrando system also guarantees a 100% conformity of the complete automation system with the FDA regulations (Food and Drug Administration), especially with the regulation 21 CFR part 11, electronic records and signatures.

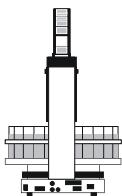
There are exchangeable standard sample racks available for many vessel dimensions. Freely selectable special beaker positions can be defined for e.g. rinsing or conditioning beakers on every rack.

The equipment with a 786 Swing Head allows to process a large number of samples in one single sample series. The robotic arms for the 786 Swing Head make it possible to move to any given point on a sample rack. This way the number (a maximum of 999 rack positions) and sequencing of the samples is almost unlimited.

Customer-specific special racks for individual requirements can be fabricated upon request.

### 1.2.1 Model versions

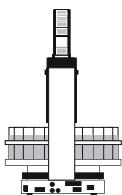
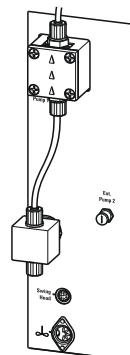
The 855 Robotic Titrosampler is available in the following versions with different components.



#### 2.855.0010

1-tower version

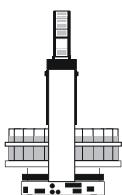
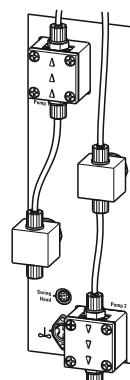
- 1 membrane pump and 1 valve
- 1 connector for an external pump
- 1 stirrer connector (tower stirrer)
- 1 786 Swing Head
- 1 measuring interface
- 3 MSB connectors for dosing devices, Remote Box or stirrers
- 2 USB connectors
- 1 connector "Controller" for Touch Control or PC



#### 2.855.0020

1-tower version

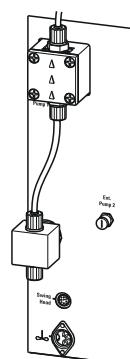
- 2 membrane pumps and 2 valves
- 1 stirrer connector (tower stirrer)
- 1 786 Swing Head
- 1 measuring interface
- 3 MSB connectors for dosing devices, Remote Box or stirrers
- 2 USB connectors
- 1 connector "Controller" for Touch Control or PC

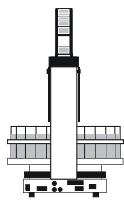


#### 2.855.0030

1-tower version

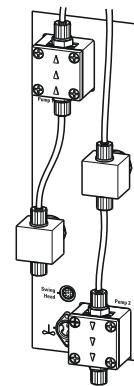
- 1 membrane pump and 1 valve
- 1 connector for an external pump
- 1 stirrer connector (tower stirrer)
- 1 Swing Head connector
- 1 measuring interface
- 3 MSB connectors for dosing devices, Remote Box or stirrers
- 2 USB connectors
- 1 connector "Controller" for Touch Control or PC



**2.855.0040**

1-tower version

- 2 membrane pumps and 2 valves
- 1 stirrer connector (tower stirrer)
- 1 Swing Head connector
- 1 measuring interface
- 3 MSB connectors for dosing devices, Remote Box or stirrers
- 2 USB connectors
- 1 connector "Controller" for Touch Control or PC

**1.2.2 Instrument components**

The 855 Robotic Titrosampler has the following components:

- **Turntable**

For sample racks with a diameter of up to 48 cm.

- **One tower with lift**

The 2.855.0010 and 2.855.0020 versions with mounted 786 Swing Head. The 2.855.0030 and 2.855.0040 versions can be upgraded with a Swing Head. Any robotic arm can be mounted.

- **One or two membrane pumps per tower**

Instead of an integrated pump, an external pump connector is available depending on the model version.

- **One stirrer connector on the tower**

For connecting a rod stirrer (802 Stirrer) or a magnetic stirrer (741 Stirrer).

- **Sensor connectors**

One connector each for:

- potentiometric electrodes (pH, ISE, metal)
- reference electrodes
- polarizable electrodes
- temperature sensors (Pt1000 or NTC)

- **Two USB connectors**

For connecting a printer, barcode reader or other control instruments (Titrando, Dosing Interface etc.).

- **Three MSB connectors (Metrohm Serial Bus)**

For connecting dosing devices (Dosimat with exchange unit or Dosino with dosing unit), stirrers or Remote Boxes.

**1.2.3 Intended use**

The 855 Robotic Titrosampler is designed for usage as an automation system in analytical laboratories or in factories that fulfill the specified ambient conditions (*see chapter 7.7, page 58*). It is **not** suitable for usage in biochemical, biological or medical environments in its basic equipment version.

This instrument is suitable for processing chemicals and flammable samples. Usage of the 855 Robotic Titrosampler therefore requires the user to have basic knowledge and experience in handling toxic and caustic substances. Knowledge with respect to the application of the fire prevention measures prescribed for laboratories is also mandatory.

## 1.3 About the documentation



### CAUTION

Please read through this documentation carefully before putting the instrument into operation. The documentation contains information and warnings which the user must follow in order to ensure safe operation of the instrument.

### 1.3.1 Symbols and conventions

The following symbols and formatting may appear in this documentation:

(5-12)

#### Cross-reference to figure legend

The first number refers to the figure number, the second to the instrument part in the figure.

1

#### Instruction step

Carry out these steps in the sequence shown.

**Method**

**Dialog text, parameter** in the software

**File ▶ New**

Menu or menu item

**[Next]**

**Button or key**



#### WARNING

This symbol draws attention to a possible life-threatening hazard or risk of injury.



#### WARNING

This symbol draws attention to a possible hazard due to electrical current.



#### WARNING

This symbol draws attention to a possible hazard due to heat or hot instrument parts.



## **WARNING**

This symbol draws attention to a possible biological hazard.



## **CAUTION**

This symbol draws attention to possible damage to instruments or instrument parts.



## **NOTE**

This symbol highlights additional information and tips.

## **1.4 Safety instructions**

### **1.4.1 General notes on safety**



**WARNING**

Operate this instrument only according to the information contained in this documentation.

This instrument left the factory in a flawless state in terms of technical safety. To maintain this state and ensure non-hazardous operation of the instrument, the following instructions must be observed carefully.

### **1.4.2 Electrical safety**

The electrical safety when working with the instrument is ensured as part of the international standard IEC 61010.



## **WARNING**

Only personnel qualified by Metrohm are authorized to carry out service work on electronic components.



WARNING

Never open the housing of the instrument. The instrument could be damaged by this. There is also a risk of serious injury if live components are touched.

There are no parts inside the housing which can be serviced or replaced by the user.

### Supply voltage



#### WARNING

An incorrect supply voltage can damage the instrument.

Only operate this instrument with a supply voltage specified for it (see rear panel of the instrument).

### Protection against electrostatic charges



#### WARNING

Electronic components are sensitive to electrostatic charges and can be destroyed by discharges.

Do not fail to pull the power cord out of the power socket before you set up or disconnect electrical plug connections at the rear of the instrument.

### 1.4.3 Tubing and capillary connections



#### CAUTION

Leaks in tubing and capillary connections are a safety risk. Tighten all connections well by hand. Avoid applying excessive force to tubing connections. Damaged tubing ends lead to leakage. Appropriate tools can be used to loosen connections.

Check the connections regularly for leakage. If the instrument is used mainly in unattended operation, then weekly inspections are mandatory.

### 1.4.4 Personnel safety



#### WARNING

Wear protective goggles and working clothes suitable for laboratory work while operating the 855 Robotic Titrosampler. It is also advisable to wear gloves when caustic liquids are used or in situations where glass vessels could break.



### **WARNING**

---

Always install the safety shield supplied with the equipment before using the instrument for the first time. Pre-installed safety shields are not allowed to be removed.

The 855 Robotic Titrosampler may not be operated without a safety shield!



### **WARNING**

---

Personnel are not permitted to reach into the working area of the instrument while operations are running!

A **considerable risk of injury** exists for the user.



### **WARNING**

---

In the event of a possible blockage of a drive, the power plug must be pulled out of the socket immediately. Do not attempt to free jammed sample vessels or other parts while the device is switched on. Blockages can only be cleared when the instrument is in a voltage-free status; this action generally involves a **considerable risk of injury**.



### **WARNING**

---

The 855 Robotic Titrosampler is **not** suitable for utilization in biochemical, biological or medical environments in its basic equipment version.

Appropriate protective measures must be implemented in the event that potentially infectious samples or reagents are being processed.

#### 1.4.5 Flammable solvents and chemicals

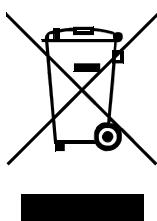


##### WARNING

All relevant safety measures are to be observed when working with flammable solvents and chemicals.

- Set up the instrument in a well-ventilated location (e.g. fume cupboard).
- Keep all sources of flame far from the workplace.
- Clean up spilled liquids and solids immediately.
- Follow the safety instructions of the chemical manufacturer.

#### 1.4.6 Recycling and disposal



This product is covered by European Directive 2012/19/EU, WEEE – Waste Electrical and Electronic Equipment.

The correct disposal of your old instrument will help to prevent negative effects on the environment and public health.

More details about the disposal of your old instrument can be obtained from your local authorities, from waste disposal companies or from your local dealer.



## 2 Overview of the instrument

### 2.1 Front and rear

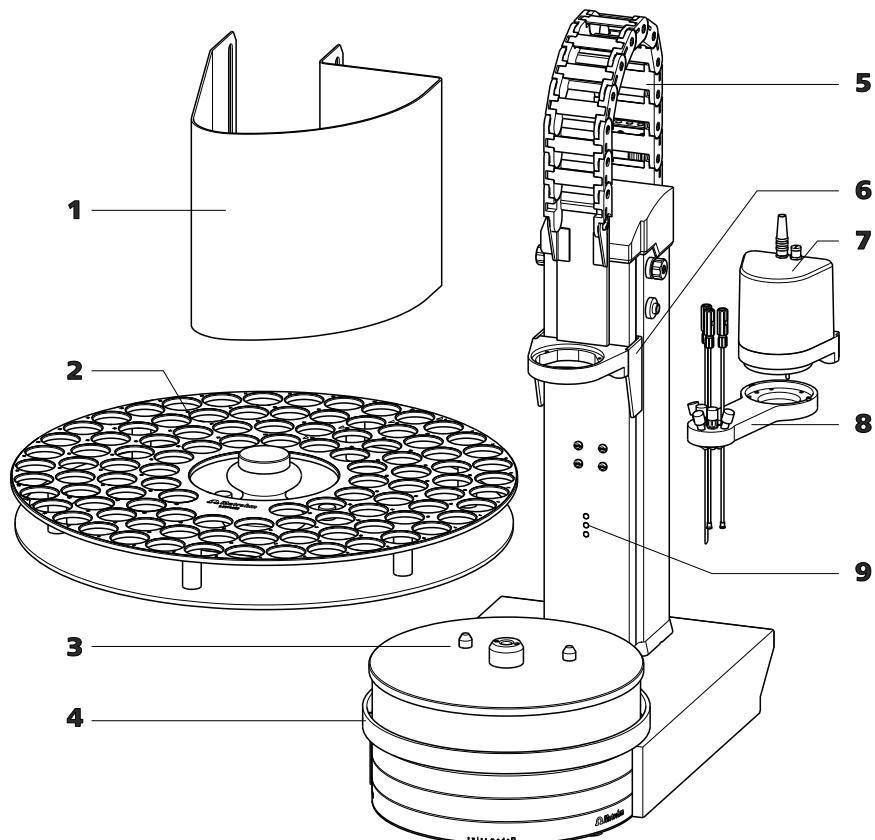


Figure 2 Front 855 Robotic Titrosampler

**1 Safety shield (6.2751.100)**

Other models, see chap. Accessories.

**3 Turntable**

With guide bolts.

**5 Guide chain**

For cables and tubings.

**7 786 Swing Head (2.786.0020)**

Drive for the robotic arm.

**9 Beaker sensor**

**2 Sample rack (6.2041.800)**

Other models, see chap. Accessories.

**4 Assembly rail**

For magnetic stirrer (741 Stirrer).

**6 Lift**

With titration head holder.

**8 Robotic arm (6.1462.050)**

With aspiration and dosing tips.

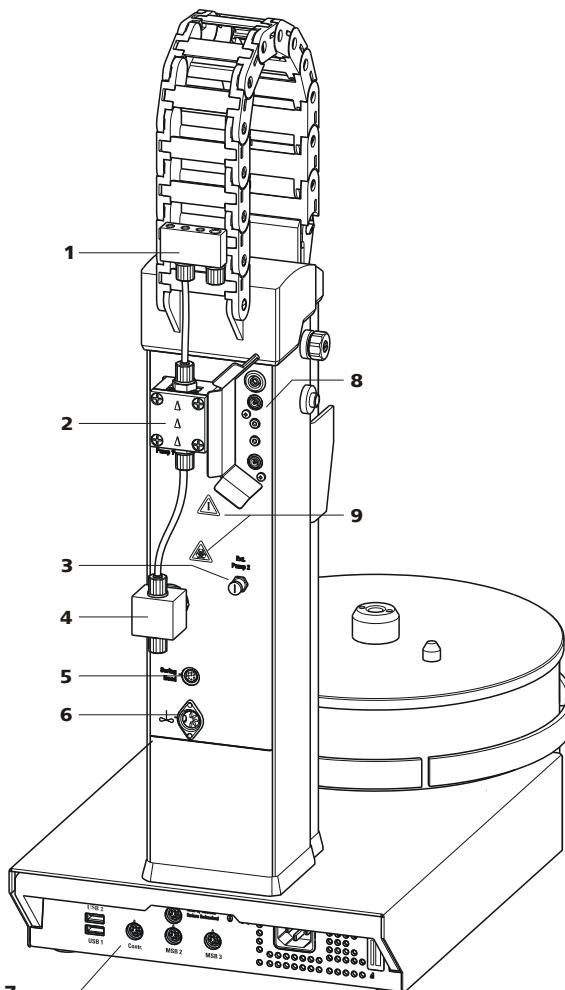


Figure 3 Rear 855 Robotic Titrosampler

#### **1 Distributor**

For rinsing equipment.

#### **2 Membrane pump**

Pump 1.

#### **3 Pump connector**

Pump 2. For external pumps (e.g. 772 Pump Unit or 823 Pump Unit).

#### **4 Pump valve**

#### **5 Connector "Swing Head"**

Mini DIN socket (9-pin).

#### **6 Stirrer connector**

DIN socket. For rod stirrer (802 Stirrer) or magnetic stirrer (741 Stirrer).

#### **7 Back panel with connectors**

#### **8 Measuring interface**

With various measuring inputs.

#### **9 Warning symbols**

See chapter *Safety instructions*.



## 2.2 Back panel

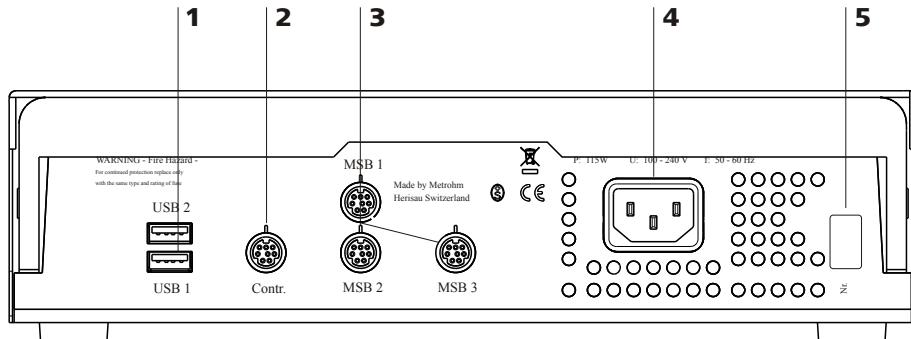


Figure 4 Connector strip

**1 USB connector (USB 1 and USB 2)**

**2 Connector (Controller)**

For the connection to the PC or Touch Control.

**3 MSB connector (MSB 1 to MSB 3)**

For stirrers, dosing devices, Remote Box.

**4 Power socket**

**5 Type plate**

Contains specifications concerning supply voltage and serial number.

## 2.3 Sensor connectors

The connectors for electrodes and temperature sensors are on the rear of the tower.

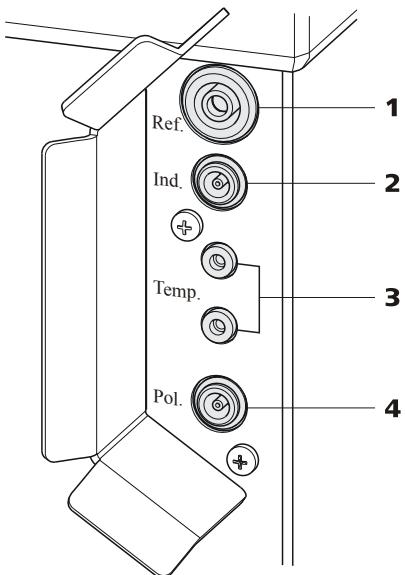


Figure 5 Sensor connectors

**1 Electrode connector (Ref.)**

For connecting reference electrodes, e.g. Ag/AgCl reference electrode. Socket B, 4 mm.

**3 Temperature sensor connector (Temp.)**

For connecting temperature sensors (Pt1000 or NTC). Two B sockets, 2 mm.

**2 Electrode connector (Ind.)**

For connecting pH, metal or ion-selective electrodes with integrated or separate reference electrode. Socket F.

**4 Electrode connector (Pol.)**

For connecting polarizable electrodes, e.g. double Pt electrodes. Socket F.

## 2.4 Sample racks

A sample rack is a turntable that acts as a receptacle for sample vessels. Various types of sample racks are available for different numbers and types of sample vessels.

The 855 Robotic Titrosampler requires sample racks with up to a maximum of **48 cm diameter**.

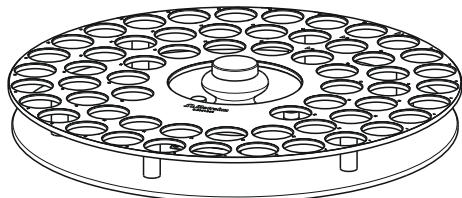


Figure 6 Sample rack 6.2041.840

Other user-defined sample racks can be supplied upon request and the required rack data can be loaded and configured in the control software. Any arrangement of rack positions is possible.



### Magnet codes

Every single sample rack can be unambiguously identified by means of a magnet code. The Sample Processor can thus recognize automatically which rack is attached.

When replacing a sample rack, this should first be returned to starting position using the **[Reset rack]** function (see "Manual Operation" in the control software).

This will enable an unambiguous recognition of the rack and thus the correct positioning of the beaker. A positioning table is assigned to each rack type in which each rack position is defined.

## 3 Installation

### 3.1 Setting up the instrument

#### 3.1.1 Packaging

The instrument is supplied in protective packaging together with the separately packed accessories. Keep this packaging, as only this ensures safe transportation of the instrument.

#### 3.1.2 Checks

Immediately after receipt, check whether the shipment has arrived complete and without damage by comparing it with the delivery note.

#### 3.1.3 Location

The instrument has been developed for operation indoors and may not be used in explosive environments.

Place the instrument in a location of the laboratory which is suitable for operation and free of vibrations and which provides protection against corrosive atmosphere and contamination by chemicals.

The instrument should be protected against excessive temperature fluctuations and direct sunlight.

### 3.2 Preparing the Sample Processor

#### 3.2.1 Connecting the instrument to the power grid



##### **WARNING**

##### **Electric shock from electrical potential**

Risk of injury by touching live components or through moisture on live parts.

- Never open the housing of the instrument while the power cord is still connected.
- Protect live parts (e.g. power supply unit, power cord, connection sockets) against moisture.
- Unplug the power plug immediately if you suspect that moisture has gotten inside the instrument.
- Only personnel who have been issued Metrohm qualifications may perform service and repair work on electrical and electronic parts.



### Connecting the power cord

#### Accessories

Power cord with the following specifications:

- Length: max. 2 m
- Number of cores: 3, with protective conductor
- Instrument plug: IEC 60320 type C13
- Conductor cross-section 3x min. 0.75 mm<sup>2</sup> / 18 AWG
- Power plug:
  - according to customer requirement (6.2122.XX0)
  - min. 10 A



#### NOTICE

Do not use a not permitted power cord!

#### 1 Plugging in the power cord

- Plug the power cord into the instrument's power socket.
- Connect the power cord to the power grid.

## 3.3 Connecting a computer

The 855 Robotic Titrosampler requires a USB connection to a computer in order to be able to be controlled by a computer software. Using a 6.2151.000 controller cable, the instrument can be connected directly, either to a USB socket on a computer, to a connected USB hub or to a different Metrohm control instrument.

You need administrator rights for the installation of driver software and control software on your computer.

#### Cable connection and driver installation

A driver installation is required in order to ensure that the 855 Robotic Titrosampler is recognized by the computer software. To accomplish this, you must comply with the procedures specified. The following steps are necessary:

#### 1 Install the software

- Insert the computer software installation CD and carry out the installation program directions.
- Exit the program if you have started it after the installation.

## 2 Establishing the cable connections

- Connect all peripheral devices to the instrument, *see chapter 3.13, page 33*.
- Connect the instrument to the power grid if you have not already done this (*see chapter 3.2.1, page 15*).
- Connect the instrument to a USB connector (type A) of your computer (see manual of your computer). The 6.2151.000 cable is used for this purpose.

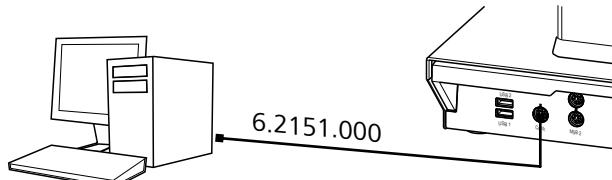


Figure 7 Connecting the computer

The instrument is recognized. Depending on the version of the Windows operating system used, the driver installation proceeds differently afterwards. Either the necessary driver software is installed automatically or an installation wizard is started.

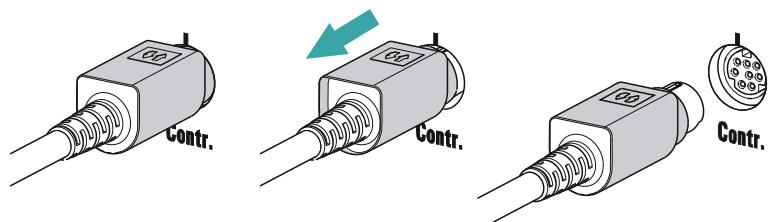
## 3 Follow the instructions of the installation wizard.

If problems should occur during installation, contact your company's IT support team.



### NOTICE

The plug on the instrument end of the 6.2151.000 controller cable is protected against accidental disconnection by means of a pull-out protection feature. If you wish to pull out the plug, you first need to pull back the outer plug sleeve marked with arrows.



## Registering and configuring the instrument in the computer software

The instrument must be registered in the configuration of your computer software. Once that has been done, you can then configure it according to your requirements. Proceed as follows:



## 1 Setting up the instrument

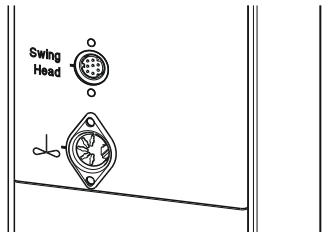
- Start the computer software.  
The instrument is automatically recognized. The configuration dialog for the instrument is displayed.
  - Make configuration settings for the instrument and its connectors.

More detailed information concerning the configuration of the instrument can be found in the documentation for the respective computer software.

## 3.4 Connecting the Swing Head

Take care to ensure that the Swing Head is connected before the 2.855.0010 and 2.855.0020 instrument versions are set to work. Check the connection cable.

The connection socket (Mini DIN) for the Swing Head drive is located on the rear of the tower above the stirrer connector.



*Figure 8 Connecting the Swing Head*

If the Swing Head is not connected, connect it as follows:

## 1 Plugging in the cable

- Guide the connection cable of the Swing Head through the guide chain of the tower (*see chapter 3.9, page 27*).
  - Plug the Mini DIN plug into the socket 'Swing Head'.

## Tower configuration

Make sure that the correct axial distance is entered when configuring the tower. The axial distance depends on whether the 855 Robotic Titrosampler is used with or without Swing Head. The correct axial distance is shown in the following table.

Table 1 Axial distance

| <b>Operation</b>   | <b>Axial distance</b> |
|--------------------|-----------------------|
| with Swing Head    | 196 mm                |
| without Swing Head | 166 mm                |

### 3.5 Configuring the robotic arm

A variety of differently constructed robotic arms is available for enabling a wide range of applications. They differ from one another in their geometric sizes, e.g. swing radius or maximum permissible swing angle. The configuration data must be entered in the Sample Processor or in the control software **prior to the assembly of the robotic arm**. The data required is engraved on the underside of the robotic arm. Examples of the most common robotic arms are shown in the illustration below.

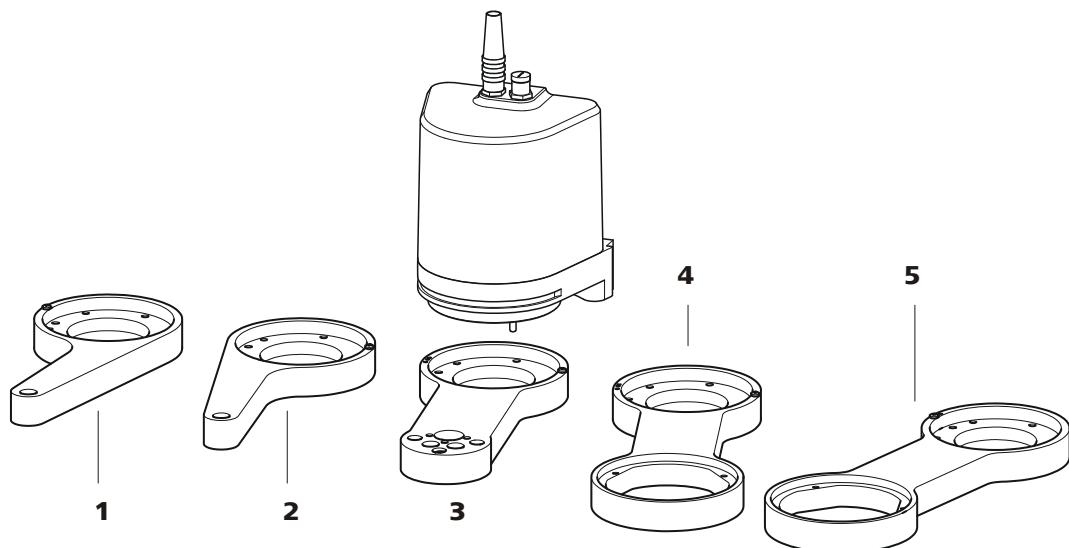


Figure 9 Robotic arms - standard model versions:

**1 Transfer robotic arm (6.1462.030)**

For sample transfer, left-swinging.

**2 Transfer robotic arm (6.1462.040)**

For sample transfer, right-swinging.

**3 Titration robotic arm (6.1462.050)**

With titration head, left-/right-swinging \*).

**4 Macro robotic arm (6.1462.060)**

With holder for a 6.1458.XXX titration head insert, left-swinging.

**5 Macro robotic arm (6.1462.070)**

With holder for a 6.1458.XXX titration head insert, right-swinging.

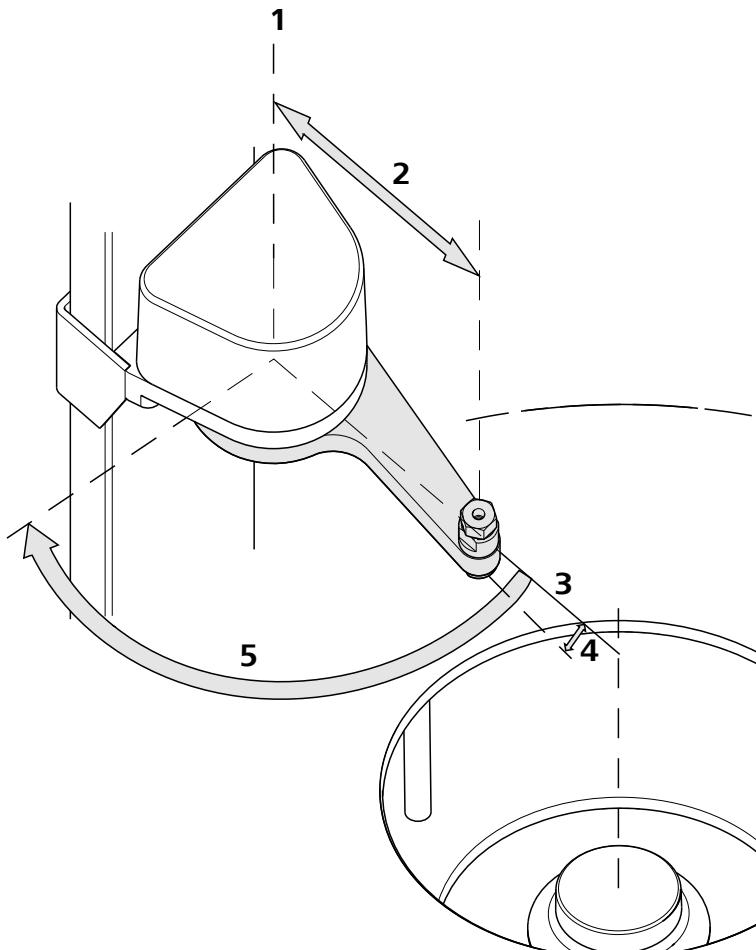
\*) can be mounted in two ways



**NOTICE**

A detailed list of the available robotic arms, along with the necessary configuration data, can be found in *Chapter Robotic arms, page 51ff.*

The following figure illustrates the most important configuration data that needs to be set in the control software to ensure correct usage of a robotic arm (left-swinging, here).



*Figure 10 Configuration data of the robotic arms*

|          |  |
|----------|--|
| <b>1</b> | <b>Swing axis</b><br>This runs through the middle of the Swing Head drive.   |
| <b>2</b> | <b>Swing radius</b><br>This is determined by the length of the robotic arm. The radius runs from the axis of rotation to the midpoint of the tip of the robotic arm.         |
| <b>3</b> | <b>Source axis</b><br>This runs from the swing axis to the midpoint of the sample rack and marks the initial position of the robotic arm.                                    |
| <b>4</b> | <b>Swing offset</b><br>This determines the 0° position of the robotic arm.   |
| <b>5</b> | <b>Max. swing angle</b><br>This stands for the swing range that the robotic arm can reach. The range runs from the source axis to the maximum possible robotic arm position. |

### Swing direction

Left-swinging (**swing direction +**) or right-swinging (**swing direction -**) model versions are available as different types of robotic arms. Left-swinging means swinging from the initial position (pointing towards the middle of the rack) outwards to the left.

In the case of a Sample Processor with two towers, a right-swinging robotic arm must be mounted on Tower 1, a left-swinging robotic arm on Tower 2. If the alignment is incorrect, the two robotic arms could possibly come into contact with one another, resulting in damage to the drives.

## 3.6 Mounting the robotic arm

Depending on the model, robotic arms can be mounted as either right-swinging or left-swinging. The position of the limitation screw of the robotic arm must be taken into account during assembly. The limitation screw must face the tower of the Sample Processor when mounting the robotic arm. The following illustration shows on the left the position of the limitation screw on a right-swinging robotic arm (**Position 1**) and on the right on a left-swinging robotic arm (**Position 2**).

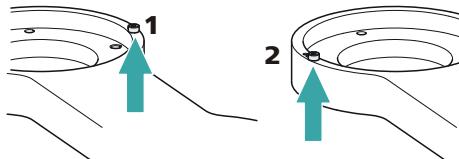


Figure 11 Limitation screw on the robotic arm

For robotic arms which can be mounted in two different ways (e.g. 6.1462.050), the limitation screw can be fitted in accordance with the required assembly direction (see above).



#### NOTICE

The configuration data of a robotic arm must be configured in the control software **before it is mounted** (see chapter 3.5, page 19).

### Mounting the robotic arm

The mounting of a robotic arm on the Swing Head is described here, taking as an example a 6.1462.070 robotic arm for titration and a 6.1458.040 titration head insert. Initialize the Sample Processor before mounting.



After the initialization of the Sample Processor, the drive disk of the Swing Head is positioned as though the robotic arm were located in the outermost position.

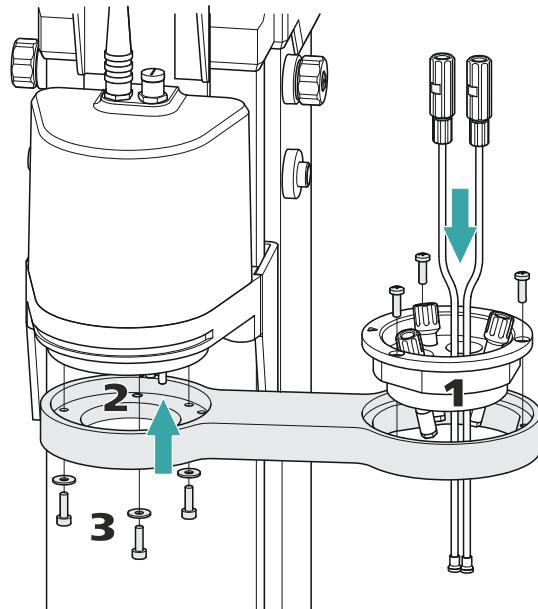


Figure 12 Mounting the robotic arm

Mount the robotic arm as follows:

**1** Place the **6.1458.040 titration head insert** in the opening of the robotic arm. The marking on the edge must be closer to the Swing Head. Tighten the titration head insert with the provided screws.

**2** Hold the robotic arm in such a way that the opening faces to the right. While doing so, rotate the robotic arm outwards as far as possible, i.e. towards the tower - see above. Slip the robotic arm from below over the guide bolts of the drive disk of the Swing Head.



#### NOTICE

Take care not to twist the drive disk and thereby put strain on the drive.

**3** Tighten the robotic arm to the Swing Head with the screws and washers supplied.

### 3.7 Robotic arms with beaker sensor

For safety reasons, the presence of a beaker on the sample rack of a Sample Processor can be detected. Some robotic arm model versions are therefore equipped with a beaker sensor.

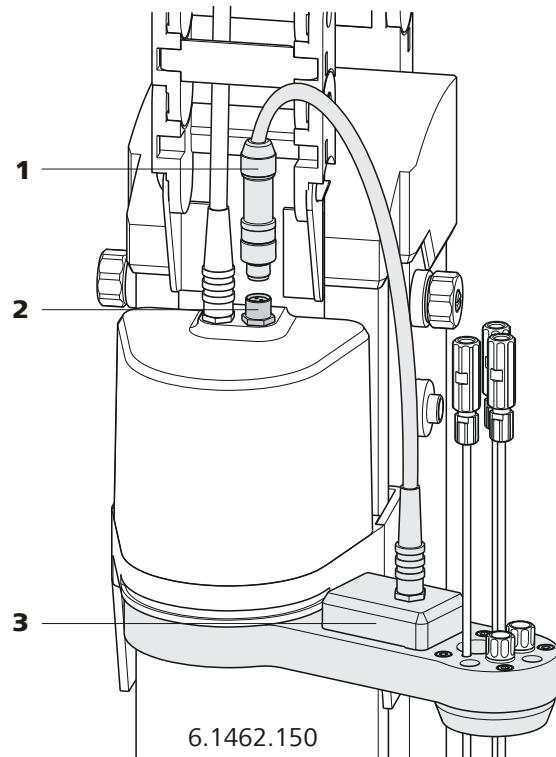


Figure 13 Connecting a beaker sensor (for example 6.1462.150)

**1 Plug of the connection cable**

**2 Connection socket on the 786 Swing Head**

**3 Beaker sensor**

Contact sensor in accordance with the Piezo principle

A robotic arm with beaker sensor is mounted as described on *page 21*. The connection of the sensor cable must take place while the instrument is switched off.

The beaker sensor is automatically recognized when switching on the instrument.

#### Functioning of the beaker sensor

If the beaker sensor of the robotic arm is activated, then the lift of the Sample Processor will move automatically into its work position after a MOVE command. The presence of the sample vessel is checked by the robotic arm setting down on top of it.



No separate LIFT command is required in such cases.



#### NOTICE

The work position of the lift must be configured in such a way that the robotic arm is in place on the sample vessel. The robotic arm must bend very slightly while doing so, so that the Piezo sensor will generate a signal.

## 3.8 Installing the rinsing and aspiration equipment

Various tubings are necessary for rinsing the electrode and the dosing tips as well as for aspirating the sample solution after the titration. First, mount the tubings on the distributor.

### Mounting the rinsing and aspiration tubings

Install the tubings as follows:

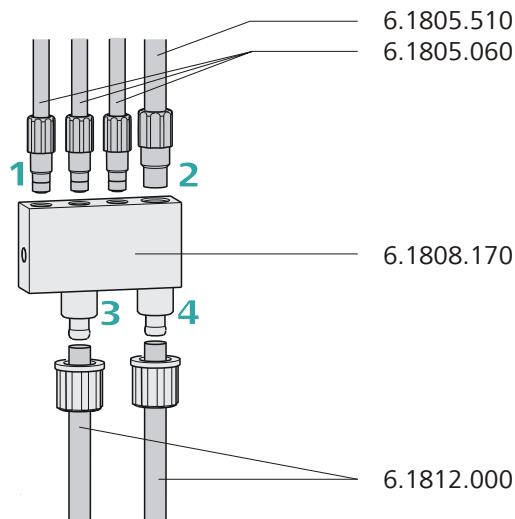


Figure 14 Mounting the rinsing and aspiration tubings

#### 1 Mounting the rinsing tubing

- Manually tighten the three **6.1805.060 FEP tubings** (60 cm) in the M6 bore holes of the distributor. Place the tubings into the guide chain (*see chapter 3.9, page 27*).  
These are the feed lines for the spray nozzles.

#### 2 Mounting the aspiration tubing

- Manually tighten the **6.1805.510 FEP aspiration tubing** (60 cm) in the M8 bore hole of the distributor.

### 3 Mounting the feed line for the rinsing liquid

- Remove the union nut of the left-hand connector of the distributor and guide it over the end of a **6.1812.000 PTFE tubing**. You may have to widen the tubing end in order to be able to better mount the tubing, see note below. Pull the end of the tubing over the connection nipple of the distributor and fasten in place with the union nut.  
The tubing leads to the rinsing pump (**Pump 1**) and can be cut to the correct length.



#### NOTICE

The opening of the tubing may need to be widened with a pointed object (e.g. with a Phillips screwdriver).

A piece of sandpaper may be used to get a better grip on the tubing.

Do not widen the tubing end before having slid the union nut onto the tubing.

### 4 Mounting the outlet tubing

- Remove the union nut of the right-hand connector of the distributor and guide it over the end of the **6.1812.000 PTFE tubing**. Pull the end of the tubing over the connection nipple of the distributor and fasten in place with the union nut.  
The tubing leads to the aspiration pump (**Pump 2**) and can be cut to the correct length.

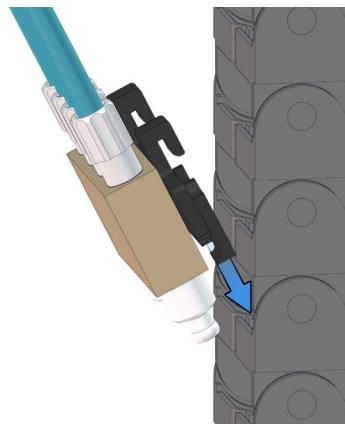


## Mounting the distributor

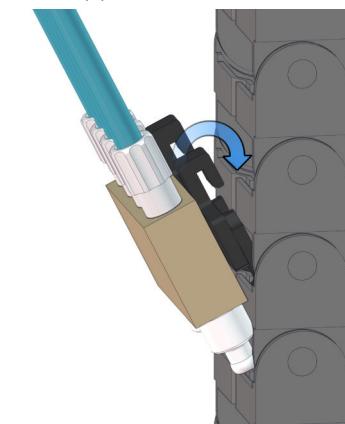
Proceed as follows to install the 6.1808.170 distributor on the guide chain:

### 1 Attaching the distributor

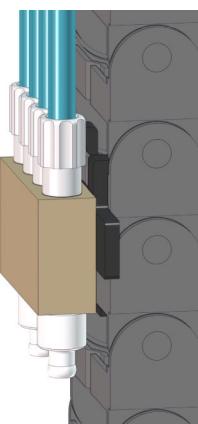
- Insert the bottom part of the distributor holder between two clips of the chain links. The tubing can remain connected.



- Insert the upper hook of the holder in the upper clip.



- Let the bottom part of the holder snap in the bottom clip.



**2 Fixing the rinsing tubings**

- Place the rinsing tubings into the guide chain (*see chapter 3.9, page 27*).

## 3.9 Placing tubing and cables in the guide chain

Tubing and cables can be placed in the guide chain.

The guide chain contains a firmly installed clip on each chain link.

**CAUTION**

When mounting tubing and cables, make sure that there is no traction on the drives while moving the lift or swinging the robotic arm. Traction on the drive can overload and damage the drive.

If a robotic arm is used, we recommend placing the tubing and cables only above the third chain link in the guide chain to prevent traction on the drives.

Do **not** or only partially place rigid tubings, as for example aspiration tubings made of PTFE, into the guide chain.

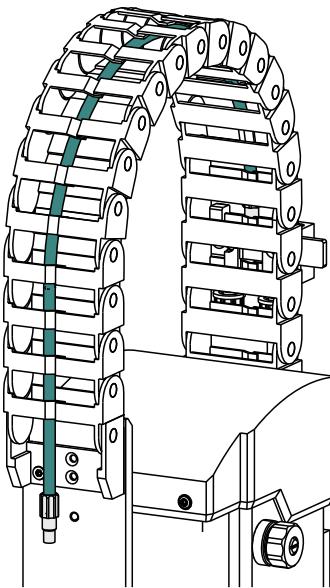
**NOTICE**

Make sure that tubing and cables do not kink.

Inserting and removing the tubing and cables requires no tools.

**1 Placing tubing and cables**

- Press one side of the clip downwards and place tubing or cables in the guide chain.



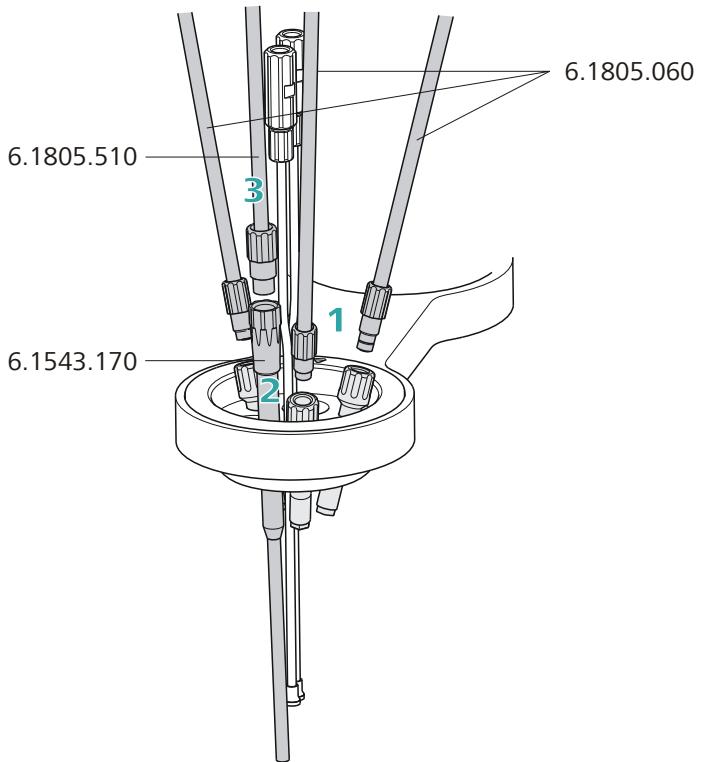
## 2 Removing tubing and cables

- Press one side of the clip downwards and remove tubing or cables from the guide chain.

# 3.10 Equipping the titration head

## Mounting the rinsing and aspiration tubings

Example of a 6.1462.070 robotic arm with 6.1458.040 titration head.



*Figure 15 Installing the rinsing tubings and the aspiration tip*

Proceed as follows:

### 1 Connecting the rinsing nozzles

- Connect the three rinsing tubings that are already connected to the distributor on the tower to the preinstalled rinsing nozzles on the titration head.

### 2 Inserting the aspiration tip

- Insert the **6.1543.170 aspiration tip** into the left-side opening on the front of the titration head (only with 6.1458.040 titration head)

### 3 Connecting the aspiration tubing

- Connect the 6.1805.510 aspiration tubing already connected to the distributor with the aspiration tip.



### Inserting the stirrer and the electrode, connecting the dosing tubings

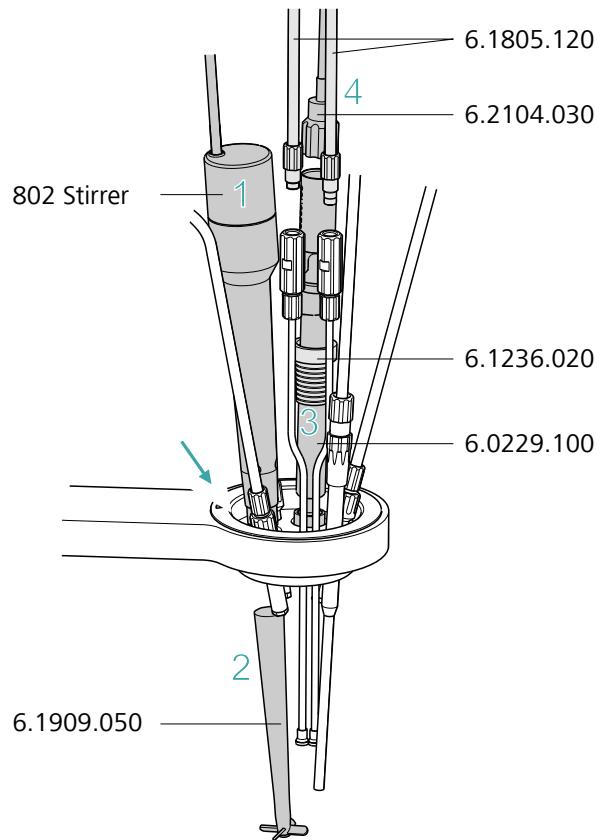


Figure 16 *Installing stirrer and electrode*

The equipment of the titration head is completed as follows:

#### 1 Inserting the rod stirrer

- Insert the rod stirrer (**802 Stirrer**) into the rear opening of the titration head (at the arrow).
- Insert the cable into the guide rail.

#### 2 Mounting the stirring propeller

- Fasten the 6.1909.0XX stirring propeller to the rod stirrer from below.

#### 3 Inserting the electrode

- Insert the electrode (e.g., a **6.0229.100 Solvotrode**) with a **6.1236.020 SGJ sleeve** into the titration head.

#### 4 Connecting the dosing tubings

- Connect two dosing tubings (e.g., 6.1805.120) to the pre-mounted dosing tips on the titration head.

### 3.11 Connecting the tower stirrer

A DIN socket for connecting a rod stirrer (**802 Stirrer**) or a magnetic stirrer (**741 Stirrer**) is located on the rear side of the tower.

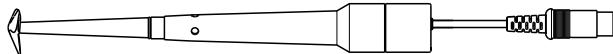


Figure 17 Rod stirrer 802 Stirrer

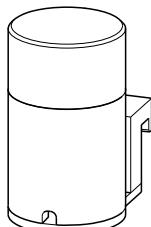


Figure 18 Magnetic stirrer 741 Stirrer

Take care to observe correct orientation of the contact pins when plugging in the stirrer connection cable. The rib on the outside of the plug must match the reference mark (on the left) on the socket.

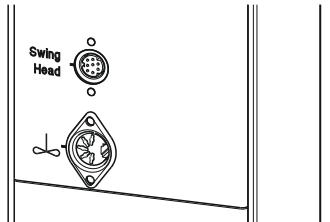


Figure 19 Connecting the tower stirrer



#### NOTICE

If an MSB stirrer is connected to the **MSB1** socket, then the stirrer connector at tower 1 cannot be used, because both sockets are controlled internally via MSB1.



## 3.12 Connecting an external pump

The model version with built-in pump allows to connect an external pump at the rear of the tower. To aspirate clear aqueous media, the **823 Membrane Pump Unit** can be used. To aspirate organic media or aqueous media containing solids, the peristaltic pump **772 Pump Unit** must be used.

### Connecting a pump

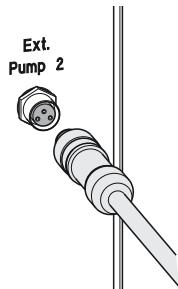
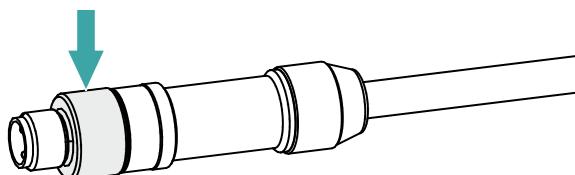


Figure 20 Connecting a pump

Connect the external pump as follows:

- 1** ▪ Plug the threaded plug of the connection cable into the connection socket **Ext. Pump 2** on the rear of the tower.  
Pay attention to the orientation of the three contact pins.  
▪ Tighten the knurled screw at the front end of the plug by hand in clockwise direction.



This secures the plug.

### 3.13 Connecting MSB devices

In order to connect MSB devices, e.g. stirrers or dosing devices, Metrohm instruments are equipped with up to a maximum of four connectors on what is referred to as the *Metrohm Serial Bus* (MSB). Various kinds of peripheral devices can be connected in sequence (in series, as a "Daisy Chain") at a single MSB connector (8-pin Mini DIN socket) and controlled simultaneously by the respective control instrument. In addition to the connection cable, stirrers and the Remote Box are each equipped with their own MSB socket for this purpose.

The following figure provides an overview of the instruments that can be connected to an MSB socket, along with a number of different cabling variations.

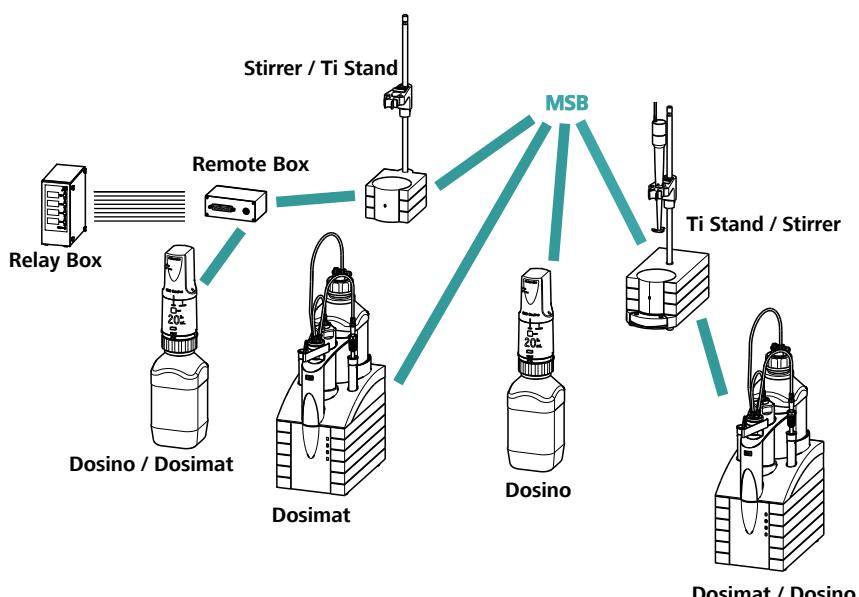


Figure 21 MSB connections

The control instrument determines which peripheral devices are supported.



#### NOTICE

When connecting MSB devices together, the following must be observed:

- Only one device of the same type can be used at a single MSB connector at one time.
- Dosing devices of the 700 Dosino and 685 Dosimat plus type cannot be connected together with other MSB devices on a shared connector. These dosing devices must be connected separately.

**CAUTION**

Exit the control software before you plug in MSB devices. When it is switched on, the control instrument automatically recognizes which device is connected to which MSB connector. The operating unit or the control software enters the connected MSB devices into the system configuration (device manager).

MSB connections can be extended with the 6.2151.010 cable. The maximum connection length permitted is 15 m.

### 3.13.1 Connecting a dosing device

Three dosing devices can be connected to the instrument.

The types of dosing devices that are supported are:

- 800 Dosino
- 700 Dosino
- 805 Dosimat
- 685 Dosimat plus

**WARNING**

If a Dosino is connected to the 855 Robotic Titrosampler, then the connection cable must be equipped with a T.2400.102 ferrite core. The ferrite core diminishes any interference voltages and thus ensures compliance with the strict EMC standards in accordance with the applicable technical standards, see EU declaration of conformity of the instrument.

Proceed as follows:

**1 Mounting the ferrite core**

- Fasten a T.2400.102 ferrite core to the Dosino connection cable close to the plug.

**2 Connecting a dosing device**

- Exit the control software.
- Connect the connection cable of the dosing device to one of the sockets marked with **MSB** on the rear of the control device.
- Start the control software.

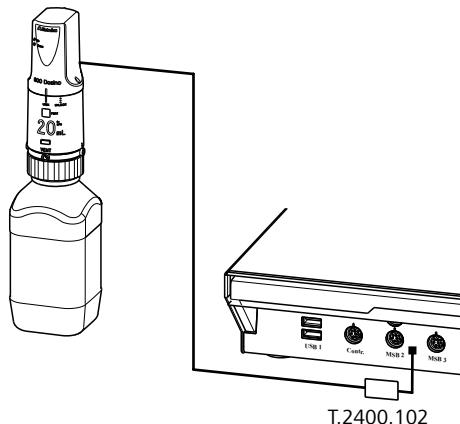


Figure 22 Connecting a dosing device

### 3.13.2 Connecting a stirrer or titration stand

You can use the following instruments:

These devices have a built-in magnetic stirrer (stirring "from below"):

- 801 Stirrer
- 803 Ti Stand

This device has no built-in magnetic stirrer (stirring "from above"):

- 804 Ti Stand with rod stirrer 802 Stirrer

Connect a stirrer or a titration stand as follows:

#### 1 Connecting the stirrer or titration stand

- Exit the control software.
- Connect the connection cable of the magnetic stirrer or of the titration stand to one of the sockets marked with **MSB** on the rear of the control instrument.
- 804 Ti Stand only: Connect the rod stirrer to the stirrer connector (socket with stirrer symbol) of the titration stand.
- Start the control software.

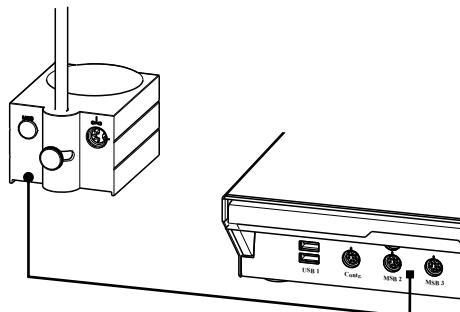


Figure 23 Connecting an MSB stirrer

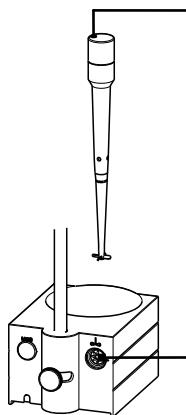


Figure 24 Connecting the rod stirrer to the titration stand



#### NOTICE

If an MSB stirrer is connected to the **MSB1** socket, then the stirrer connector at tower 1 cannot be used, because both sockets are controlled internally via MSB1. In case of a 2-tower model of a USB Sample Processor, this also applies for the **MSB2** socket and the stirrer connector on tower 2.

### 3.13.3 Connecting a Remote Box

Instruments that are controlled via remote lines and/or that send control signals via remote lines can be connected via the 6.2148.010 Remote Box. In addition to Metrohm, other instrument manufacturers also use similar connectors that make it possible to connect different instruments together. These interfaces are also frequently given the designations "TTL Logic", "I/O Control" or "Relay Control" and they generally have a signal level of 5 volts.

Control signals are understood to be electrical line statuses or electrical pulses (> 200 ms) which display the operating status of an instrument or which trigger or report an event. Sequences on a variety of instruments can thus be coordinated in a single complex automation system. However, no exchange of data is possible.

Proceed as follows:

#### 1 Connecting the Remote Box

- Exit the control software.
- Connect the Remote Box connection cable to one of the sockets marked with **MSB** on the rear of the control instrument.
- Start the control software.

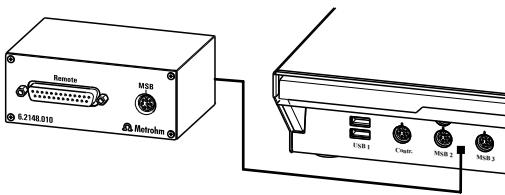


Figure 25 Connecting the Remote Box

You can connect the following instruments to the remote connector, among others:

- 849 Level Control (fill level monitoring in a canister)
- 731 Relay Box (switch box for 230/110 volt alternating current sockets and low-voltage direct current outlets)
- 843 Pump Station (for complex sample preparations or for rinsing external titration vessels)

The Remote Box also has an MSB socket at which a further MSB device, e.g. a dosing device or a stirrer, can be connected.

You will find precise information concerning the pin assignment of the interface on the Remote Box in the *appendix*.

## 3.14 Connecting USB devices

Two USB connectors (type A sockets) are available for connecting instruments with an USB interface. The 855 Robotic Titrosampler then functions as USB hub (distributor). If you wish to connect more than two USB devices, you can also use an additional, commercially available USB hub.



### NOTICE

When connecting an USB device, the control instrument automatically recognizes which device is connected. The control software enters a connected USB device automatically into the system configuration (device manager).

### 3.14.1 Connecting a barcode reader

A barcode reader is used as an aid for text and numerical input. You can connect a barcode reader with USB interface.

Connect the barcode reader as follows:

#### 1 Connecting the cables

- Insert the USB plug (type A) of the barcode reader into one of the USB sockets on the rear of the instrument.

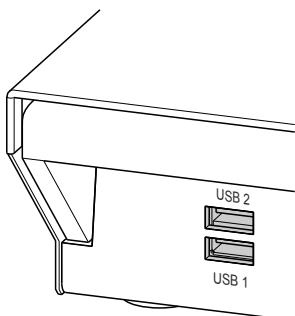


Figure 26 USB connectors

## 2 Configuring the barcode reader in the control software

- Configure the barcode reader in the configuration of the control software, as described in the online help of the software.

### Setting the barcode reader

The barcode reader requires certain basic settings. You can find instructions on how to program the barcode reader in the manual for the barcode reader. Set the barcode reader into program mode and configure the following settings:

- 1** ▪ Specify the keyboard layout for the desired country (USA, Germany, France, Spain, German-speaking Switzerland). This setting must match the setting in the control software.
  - Make sure that the Ctrl characters (ASCII 00 to 31) can be sent.
  - Set the "Preamble" (introduction) or "Prefix Code" for the ASCII character 02 (STX or Ctrl B) to be sent as the first character.
  - Set the "Postamble", "Record Suffix" or "Postfix Code" for the ASCII character 04 (EOT or Ctrl D) to be sent as the last character.
  - Close programming mode.

### 3.15 Mounting the base plate

If it is needed by an application that a determination is not carried out on the sample rack but in an external measuring cell, a stand plate can be mounted. It can be placed on the left or on the right of a tower of the 855 Robotic Titrosampler. Any accessories parts can be placed on the support rod of the stand plate.

#### Mounting the base plate

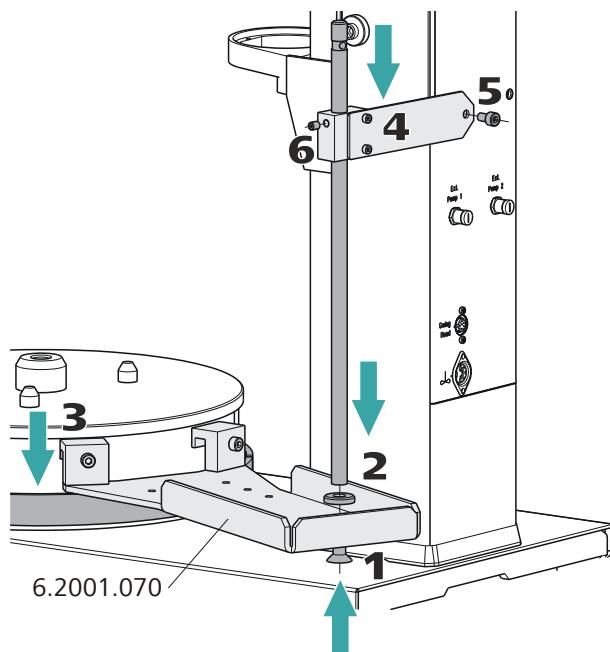


Figure 27 Mounting the base plate

Proceed as follows:

- 1** Insert the enclosed countersunk screw from below into the opening on the very back of the base plate.
- 2** Place the washer (flat side upwards) over the countersunk screw and tighten the support rod with the countersunk screw. The necessary hexagon key is enclosed with the 855 Robotic Titrosampler.
- 3** Hang the base plate to the assembly rail of the turntable with the holding clamps. Slide the whole stand plate as near to the tower as possible. Fix the holding clamps with a hexagon key to the assembly rail.

**NOTICE**

Before the stand plate is fixed to the tower, e.g. a magnetic stirrer or a measuring cell can be mounted on the support rod.

- 4** Guide the bracing from above over the support rod.
- 5** Loosen the screw for fastening the bracing on the rear panel of the tower (see figure) and fix the bracing with the enclosed hexagon screw.
- 6** Fix the bracing to the support rod with a hexagon key, see figure.

## 3.16 Mounting the drip pan

Serious damage to the instrument or a danger to the user can occur if chemicals or liquid samples are spilled.

The use of a suitable **drip pan** (6.2711.0X0) is recommended in order to avoid such incidents.

### Mounting the drip pan

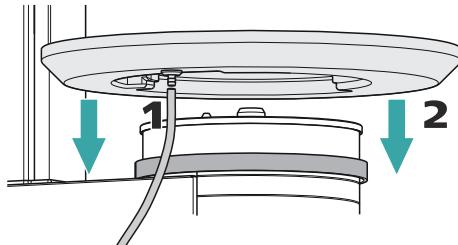


Figure 28 *Installing the drip pan*

Install the drip pan as follows:

- 1** Fasten the enclosed tubing to the drainage nipple on the drip pan and then guide the free end of the tubing into a waste container.
- 2** Place the drip pan on the assembly rail of the turntable as shown in the figure.

### 3.17 Attaching a sample rack

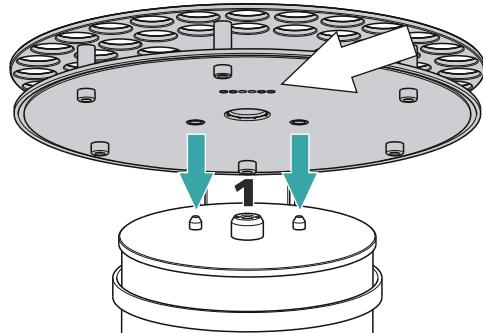


Figure 29 Attaching rack

The easiest way to put a sample rack into position is when the turntable is in the starting position.

If the instrument is switched off, then the turntable can be rotated manually into position. Both of the turntable guide bolts must be positioned so that they are pointing towards the tower.

Put the rack into place as follows:

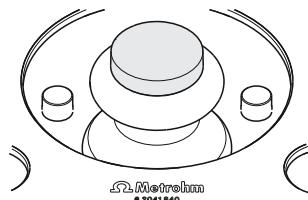
- Carefully center the rack on the turntable. The guide bolts on the turntable must engage with the openings in the bottom of the rack.



#### NOTICE

Hold the rack in such a way that the printed Metrohm logo is legible horizontally.

- Screw the fixing screw in the handle tight by rotating it clockwise.



- Carry out the **[Rack reset]** or **[Initialize rack]** function in the manual control of the control software.

The rack is moved into starting position. The magnet code of the rack is read out by the instrument during this process. The white arrow in *Figure 29* Figure indicates the position of the magnet holder. The six-



digit magnet code is used to identify the rack type. The sample positions and any special positions on the rack are defined along with the rack type.

## 3.18 Mounting the safety shield

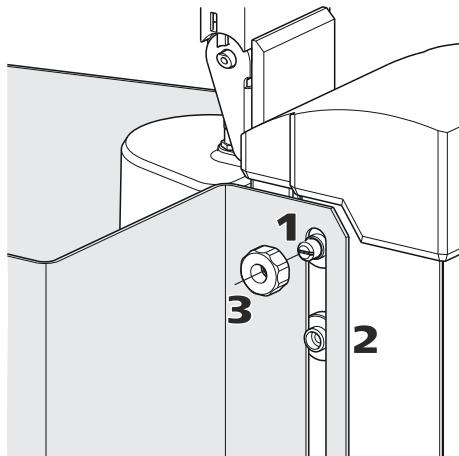
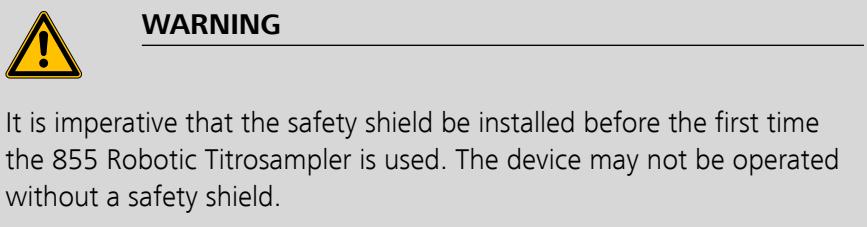


Figure 30 Mounting the safety shield

Proceed as follows.

- 1** Loosen the knurled screws on both sides of the tower.
- 2** Move the **safety shield** into position, starting from the top. Observe the corresponding illustration at the top.
- 3** Fix the safety shield in place with the knurled screws.



## NOTICE

---

You can adjust the vertical position of the safety shield at any time by loosening the screws.

The optimum vertical position meets the following criteria:

- The rack can rotate freely.
- Nobody can access the working area of the lift while the instrument is in operation.



## 4 Operation and maintenance

### 4.1 General notes

The 855 Robotic Titrosampler requires appropriate care. Excess contamination of the instrument may result in malfunctions and a reduction in the service life of the sturdy mechanical and electronic components.

Severe contamination can also have an influence on the measured results. Regular cleaning of exposed parts can prevent this to a large extent.

Spilled chemicals and solvents must be removed immediately. In particular, the power plug should be protected from contamination.

### 4.2 Care

- Check all tubing connections regularly for leaks.
- Rinse the tubing connections from time to time. The tubing must be replaced after prolonged usage.

## 5 Troubleshooting

### 5.1 Sample Processor

| Problem                                  | Cause  | Remedy   |
|--|--|--|
| <b>The instrument is not recognized.</b> | <i>Sample Processor – No USB connection.</i>                         | <ol style="list-style-type: none"> <li>1. Correctly plug in the USB connecting cable on both ends.</li> <li>2. Restart the control software or switch the Touch Control off and on again.</li> </ol> |
|  | <i>Sample Processor – Power supply of the instrument is missing.</i> | <ol style="list-style-type: none"> <li>1. Plug in the power cord on the instrument.</li> <li>2. Restart the control software or switch the Touch Control off and on again.</li> </ol>                |

### 5.2 Robotic arm

| Problem   | Cause   | Remedy   |
|---|---|--|
| <b>The robotic arm moves all the way outward and buzzes.</b>                    | <i>Sample Processor – The Swing Head is not correctly configured.</i>     | In the control software under "Configuration" (or under "Device manager" for Touch Control), enter the correct value for the <b>Swing offset</b> .                           |
|   | <i>Sample Processor – Robotic arm is mounted incorrectly.</i>             | Disconnect the power plug and dismount the robotic arm. Check the configuration of the robotic arm and mount it correctly if necessary (left-swinging ⇔ right-swinging).     |
| <b>The Swing Head either misses the rack positions totally or is inaccurate</b> | <i>Sample Processor – The Swing Head is not correctly configured.</i>     | Enter the correct values for the <b>Swing radius</b> , <b>Swing offset</b> etc. in the control software under "Configuration" (or under "Device manager" for Touch Control). |
|   | <i>Sample Processor – The axial distance is not correctly configured.</i> | Enter the correct value for the <b>Axial distance</b> in the control software under "Configuration" (or under "Device manager" for Touch Control).                           |
|   | <i>Sample Processor – The wrong rack table is being used.</i>             | Initialize the rack using the function <b>Initialize rack</b> in the "Manual control".   |



| <b>Problem</b> | <b>Cause</b>   | <b>Remedy</b>            |
|----------------|--|--------------------------|
|                | <i>Swing Head – The Swing Head drive is defective.</i> | Contact Metrohm Service. |

## 5.3 Pump

| <b>Problem</b>              | <b>Cause</b>  | <b>Remedy</b>  |
|-----------------------------|---|--|
| <b>The pump is leaking.</b> | <p><i>Sample Processor – A tubing connection is leaking.</i></p> <p><i>Canister – There is too much pressure on the pump valve.</i></p> | <p>Check the tubing connections especially between the distributor and the pump and seal tightly.</p> <ul style="list-style-type: none"> <li>▪ Make sure that the canisters are not placed on a higher level than the pump.</li> <li>▪ Check the fill level of the canisters.</li> <li>▪ Make sure that the canisters are not completely sealed (overpressure).</li> </ul> |

# 6 Appendix

## 6.1 Beaker sensor

Every tower of a Sample Processor is equipped with a beaker sensor detecting the availability of a sample vessel in front of the tower. An infrared sensor identifies devices of various materials if they are located in a correct position in front of the tower. In the rack configuration of the control instrument or the control software, **Tower** must be selected for the setting 'Beaker sensor'. This beaker test is carried out whenever a rack position is approached in a method run.

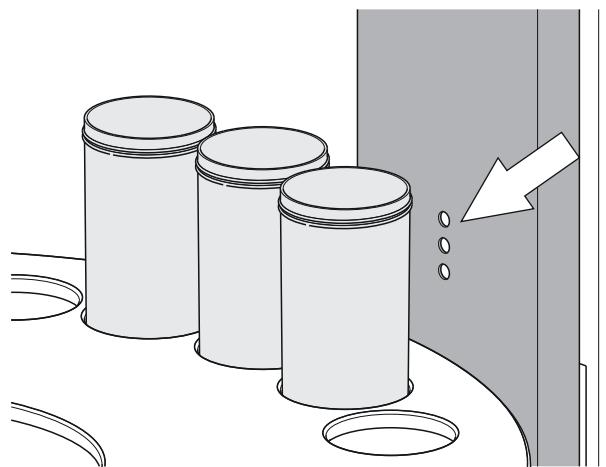


Figure 31 Beaker sensor on the tower

The beaker sensor on the tower can only be used with single-row sample racks.

## 6.2 Rinsing nozzles

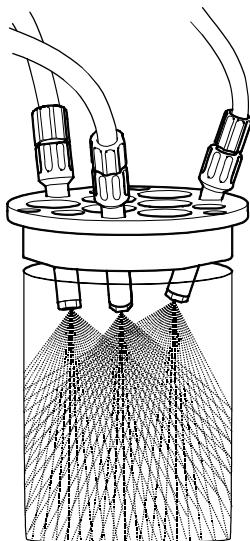
Using rinsing nozzles is very effective in order to rinse sample vessels (with sensors and buret tips) efficiently. Rinsing nozzles are available in two model versions:

- **6.2740.020 spray nozzle**

For the fine-spraying of the rinsing solution. The nozzle has a small ball at the opening. The distribution (but also the backpressure) of the rinsing liquid is clearly higher than the one of a rinsing nozzle.

- **6.2740.030 rinsing nozzle** (optionally available)

The rinsing liquid is applied as a fine jet for optimal removal of layers on electrodes and on titration accessories.

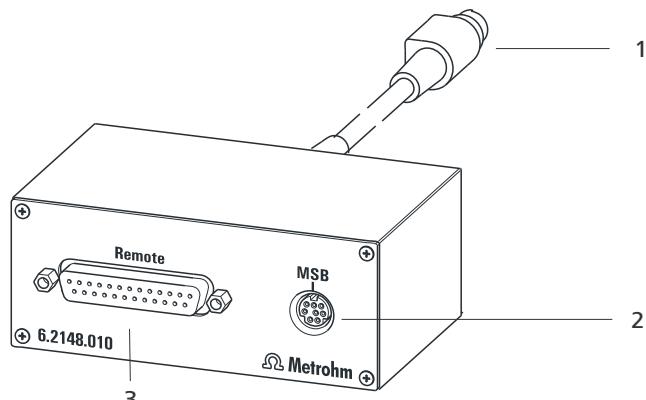


*Figure 32 Spray nozzles - Mode of operation*

The height of the nozzles can be adjusted in the titration head in order to reach an optimal rinsing effect.

## 6.3 Remote interface

The 6.2148.010 Remote Box allows devices to be controlled which cannot be connected directly to the MSB interface of the Titrosampler.



*Figure 33 Connectors of the Remote Box*

### 1 Cables

For connecting to an MSB connector of the Titrosampler.

### 2 MSB connector

Metrohm Serial Bus. For connecting external dosing devices or stirrers.

### 3 Remote connector

For connecting instruments with a remote interface.

### 6.3.1 Pin assignment of the remote interfaces

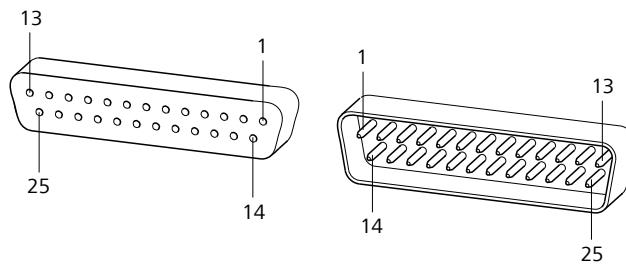
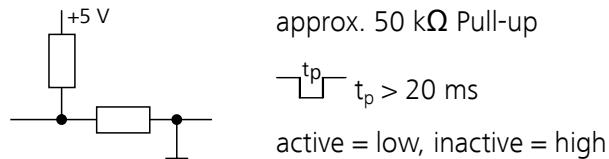


Figure 34 Pin assignment of remote socket and remote plug

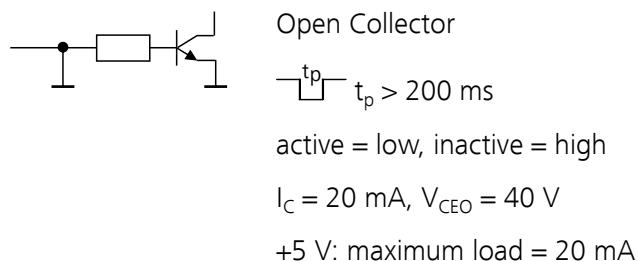
The above figure of the pin assignment of a Metrohm remote interface does not only apply for the Remote Box, but also for all Metrohm devices with 25-pin D-Sub remote connectors.

#### Inputs



The input lines can be scanned with the **SCAN** command.

#### Outputs



The output lines can be set with the **CTRL** command.

Table 2 Inputs and outputs of the remote interface

| Assignment | Pin no. | Assignment | Pin no. |
|------------|---------|------------|---------|
| Input 0    | 21      | Output 0   | 5       |
| Input 1    | 9       | Output 1   | 18      |
| Input 2    | 22      | Output 2   | 4       |
| Input 3    | 10      | Output 3   | 17      |
| Input 4    | 23      | Output 4   | 3       |
| Input 5    | 11      | Output 5   | 16      |



| Assignment    | Pin no. | Assignment | Pin no. |
|---------------|---------|------------|---------|
| Input 6       | 24      | Output 6   | 1       |
| Input 7       | 12      | Output 7   | 2       |
| 0 volts / GND | 14      | Output 8   | 6       |
| +5 volt       | 15      | Output 9   | 7       |
| 0 volts / GND | 25      | Output 10  | 8       |
|               |         | Output 11  | 13      |
|               |         | Output 12  | 19      |
|               |         | Output 13  | 20      |

## 6.4 Stirring rate

The stirring rate can be adjusted in steps from -15 to +15.

The approximate rotational speed for the internal magnetic stirrer (depends on the product version) can be calculated with the following formula:

$$\text{Rotational speed/min (r/min)} = 125 \cdot \text{Stirring rate}$$

Example:

Configured stirring rate: 8

Rotational speed in revolutions per minutes =  $125 \cdot 8 = 1,000$

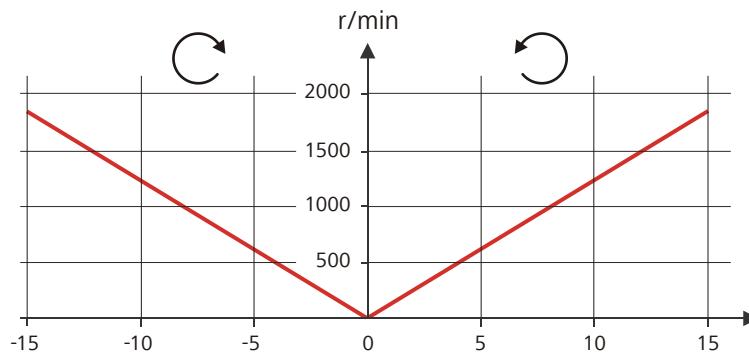


Figure 35 Rotational speed depending on the stirring rate

The information on the separately connectable 802 propeller stirrer can be found in the "802 Stirrer" manual.

## 6.5 Robotic arms

### 6.5.1 Robotic arms for titration

Table 3 Configuration data of the titration robotic arms

| Type             | 6.1462.050   | 6.1462.060   | 6.1462.070  | 6.1462.260   |
|------------------|--|--|---|--|
|                  |  6.1462.050 |  6.1462.060 |  6.1462.070 |  6.1462.260 |
| Swing direction  | +/-  | +  | -   | +  |
| Swing offset     | 0°   | -8°  | -8°   | -8°  |
| Max. swing angle | 84°  | 73°  | 73°   | 105°   |
| Swing radius     | 110 mm   | 127 mm   | 127 mm  | 110 mm   |

6.1462.050

#### Robotic arm with titration head, left or right-swinging

For titration in 75 mL sample vessels and larger.

The arm can be equipped with two microelectrodes, one propeller stirrer and three spray nozzles. Two buret tips with anti-diffusion valve and one aspiration tip with connections for M6 tubing are already retracted into the arm.

Material: PP

6.1462.060

#### Robotic arm with holder for a titration head, left-swinging

The arm can be modified to create the desired titration robotic arm by means of the installation of a titration head 6.1458.xxx.

Material: PP

6.1462.070

#### Robotic arm with holder for a titration head, right-swinging

The arm can be modified to create the desired titration robotic arm by means of the installation of a titration head 6.1458.xxx.

Material: PP



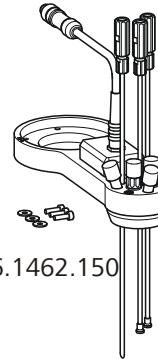
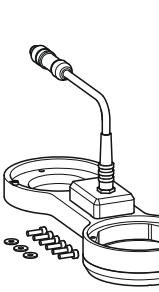
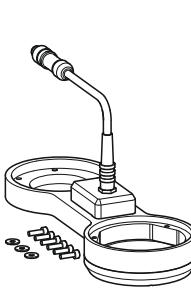
6.1462.260

### **Robotic arm with holder for a titration head, left-swinging, external**

The arm can be modified to create the desired titration robotic arm by means of the installation of a titration head 6.1458.xxx. The cutout permits movement to external positions near the rack, e.g. an external rinsing station.

Material: PVC

*Table 4 Configuration data of the robotic arms with beaker sensor*

| Type             | 6.1462.150  | 6.1462.160  | 6.1462.170   |
|------------------|---|---|--|
|                  | <br>6.1462.150 | <br>6.1462.160 | <br>6.1462.170 |
| Swing direction  | +/-   | +   | -  |
| Swing offset     | 0°  | -8°   | -8°  |
| Max. swing angle | 84°   | 73°   | 73°  |
| Swing radius     | 110 mm  | 127 mm  | 127 mm   |

6.1462.150

### **Robotic arm with titration head and beaker sensor, left or right-swinging**

For titration in 75 mL sample vessels and larger.

The arm can be equipped with two microelectrodes, one propeller stirrer and three spray nozzles. Two buret tips with anti-diffusion valve and one aspiration tip with connections for M6 tubing are already retracted into the arm.

Material: PP

6.1462.160

### **Robotic arm with holder for a titration head and beaker sensor, left-swinging**

The arm can be modified to create the desired titration robotic arm by means of the installation of a titration head 6.1458.xxx.

Material: PP

6.1462.170

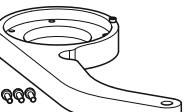
**Robotic arm with holder for a titration head and beaker sensor, right-swinging**

The arm can be modified to create the desired titration robotic arm by means of the installation of a titration head 6.1458.xxx.

Material: PP

## 6.5.2 Robotic arms for sample preparation

Table 5 Configuration data of the robotic arms for sample preparation

| Type             | 6.1462.030  | 6.1462.040  | 6.1462.090   | 6.1462.240  |
|------------------|---|---|--|---|
|                  | <br>6.1462.030 | <br>6.1462.040 | <br>6.1462.090 | <br>6.1462.240 |
| Swing direction  | +   | -   | -  | -   |
| Swing offset     | 8°  | 8°  | 8°   | -8.6°   |
| Max. swing angle | 117°  | 117°  | 117°   | 122°  |
| Swing radius     | 112 mm  | 112 mm  | 112 mm   | 149.8 mm  |

6.1462.030

**Robotic arm with transfer head, left-swinging**

Robotic arm for fully automated pipetting or dilution of liquid samples with Sample Processor Systems.

Material: PP

6.1462.040

**Robotic arm with transfer head, right-swinging**

Robotic arm for fully automated pipetting or dilution of liquid samples with Sample Processor Systems.

Material: PP

6.1462.090

**Robotic arm with Luer lock adapter, right-swinging**

For the connection of hollow needles with Luer lock connection. Suitable for the transfer of samples from sealed vials with septum seal.

Material: PP

6.1462.240

**Robotic arm with transfer head, bent, right-swinging**

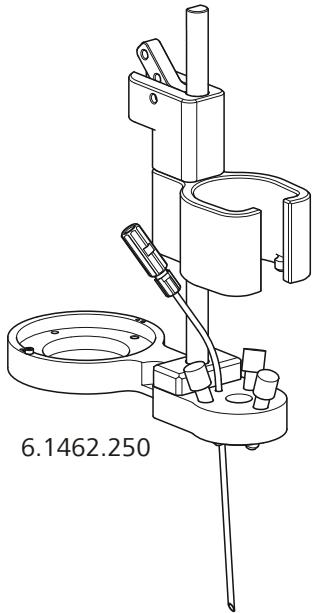
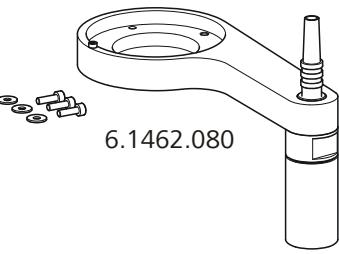
The transfer head can, when equipped with 6.1808.220 adapter, be used as a holder for various tools with Luer connection on multirow racks.



Material: PP

### 6.5.3 Robotic arms for special applications

Table 6 Configuration data of the special robotic arms

| Type             | 6.1462.250   | 6.1462.080   |
|------------------|--|--|
|                  | <br>6.1462.250 | <br>6.1462.080 |
| Swing direction  | +  | +  |
| Swing offset     | 0°   | 8°   |
| Max. swing angle | 115.5°   | 117°   |
| Swing radius     | 110 mm   | 112 mm   |

6.1462.250

#### Robotic arm as holder for a Polytron, left-swinging

The robotic arm makes it possible to use the Polytron for sample preparation on multirow sample racks. It contains one retracted buret tip for adding solvents and three spray nozzles for cleaning.

Material: PP

6.1462.080

#### Robotic arm DIS-COVER, left-swinging

Robotic arm for placing and removing sample vessel covers (75 and 250 mL) covers 6.2037.050 und 6.2037.060) on the sample rack of a Robotic Sample Processor.

Material: PP

## 7 Technical specifications

### 7.1 Measuring interface

The 855 Robotic Titrosampler has one galvanically isolated measuring interface.

The measuring cycle is 100 ms for all measuring modes.

#### 7.1.1 Potentiometry

One high-ohm measuring input (**Ind.**) for pH, redox or ISE electrodes and one reference measuring input (**Ref.**) for a separate reference electrode.

|                           |  |
|---------------------------|--|
| <i>Input resistance</i>   | > $1 \cdot 10^{12}$ $\Omega$   |
| <i>Offset current</i>     | < $1 \cdot 10^{-12}$ A (under reference conditions)  |
| <i>Measuring mode</i>     |  |
| <i>Measuring range</i>    | -20 - +20 pH   |
| <i>Resolution</i>         | 0.001 pH<br>0.1 mV   |
| <i>Measuring accuracy</i> | $\pm 0.003$ pH<br>$\pm 0.2$ mV<br>( $\pm 1$ digit, without sensor error, under reference conditions) |

#### 7.1.2 Polarizer

A measuring input (**Pol.**) for a polarizable electrode.

|                             |  |
|-----------------------------|--|
| <i>Measuring mode</i>       | Determination with adjustable polarization current   |
| <i>Ipol</i>                 |  |
| <i>Polarization current</i> | -125.0...+125.0 $\mu$ A (in steps of 2.5 $\mu$ A)<br>-125 - -121 $\mu$ A / +121 - +125 $\mu$ A: non-guaranteed values, dependent on reference voltage +2.5 V |
| <i>Measuring range</i>      | -1200 - +1200 mV   |
| <i>Resolution</i>           | 0.1 mV   |
| <i>Measuring accuracy</i>   | $\pm 0.2$ mV<br>( $\pm 1$ digit, without sensor error, under reference conditions)   |
| <i>Measuring mode</i>       | Determination with adjustable polarization voltage   |
| <i>Upol</i>                 |  |
| <i>Polarization voltage</i> | -1250 - +1250 mV (in steps of 25 mV)   |



–1250 - –1210 mV / +1210 - +1250 mV: non-guaranteed values,  
dependent on reference voltage +2.5 V

|                        |                |
|------------------------|----------------|
| <i>Measuring range</i> | –120 - +120 µA |
| <i>Resolution</i>      | 0.1 µA         |

### 7.1.3 Temperature

One measuring input (**Temp.**) for a Pt1000 or NTC temperature sensor.  
Automatic temperature compensation for NTC sensors; R (25 °C) and B value can be configured.

*Measuring range*

|        |  |
|--------|--|
| Pt1000 | –150 - +250 °C                                 |
| NTC    | –5 - +250 °C                                   |
|        | (R (25 °C) = 30,000 Ω and B (25/50) = 4,100 K) |

*Resolution*

|        |        |
|--------|--------|
| Pt1000 | 0.1 °C |
| NTC    | 0.1 °C |

*Measuring accuracy*

|        |  |
|--------|--|
| Pt1000 | ±0.2 °C<br>(Applies for measuring range –20 - +150 °C; ±1 digit; without sensor error, under reference conditions) |
| NTC    | ±0.6 °C<br>(Applies for measuring range +10 - +40 °C; ±1 digit; without sensor error, under reference conditions)  |

## 7.2 Lift and turntable

|                          |                                      |
|--------------------------|--------------------------------------|
| <i>Stroke path</i>       | 235 mm                               |
| <i>Maximum lift load</i> | approx. 30 N / 3 kg                  |
| <i>Lift rate</i>         | adjustable, 5 - 25 mm/s              |
| <i>Turntable speed</i>   | adjustable, 3 - 20 angular degrees/s |

## 7.3 Membrane pump(s) with valve

*Flow rate* > 450 mL/min  
*Pressure head* 2 m

## 7.4 786 Swing Head

*Maximum load* approx. 15 N  
*Swing rate* 10 - 55 angular degrees/s  
*Beaker sensor connector* Socket with M8 thread

## 7.5 Interfaces and connectors

|                                   |  |
|-----------------------------------|--|
| <i>Connector "Controller"</i>     | USB upstream port (9-pin Mini DIN socket) for connecting a computer for controlling the instrument.  |
| <i>MSB connectors MSB1 - MSB3</i> | Three 9-pin Mini DIN sockets for connecting dosing devices (Dosino/ Dosimat), stirrers, etc.   |
| <i>USB connectors 1/2</i>         | Two USB downstream ports (type A sockets), each 500 mA, for connecting Metrohm instruments or USB peripheral devices of other manufacturers. |
| <i>Stirrer connector</i>          | DIN socket   |
| <i>Stirring rate</i>              | 722/802 rod stirrer: 180 - 3000 rpm<br>741 magnetic stirrer: 180 - 2600 rpm<br>adjustable in 15 steps each in both directions of rotation    |
| <i>Pump connector</i>             | Two sockets with M8 thread for 772 Pump Unit or 823 Membrane Pump Unit<br>$U = 16 \pm 1 \text{ V}, I = \leq 0.8 \text{ A}$                   |
| <i>Swing Head connector</i>       | 9-pin Mini DIN socket  |



## 7.6 Power connection

|                          |             |
|--------------------------|-------------|
| <i>Voltage</i>           | 100 - 240 V |
| <i>Frequency</i>         | 50 - 60 Hz  |
| <i>Power consumption</i> | 115 W       |
| <i>Fuse</i>              | 2.0 ATH     |

## 7.7 Ambient temperature

|                               |                             |
|-------------------------------|-----------------------------|
| <i>Nominal function range</i> | 5 - 45 °C<br>Humidity < 80% |
| <i>Storage</i>                | -20 - 60 °C                 |
| <i>Transport</i>              | -40 - 60 °C                 |

## 7.8 Reference conditions

|                            |                     |
|----------------------------|---------------------|
| <i>Ambient temperature</i> | 25 °C ( $\pm 3$ °C) |
| <i>Relative humidity</i>   | $\leq 60\%$         |

## 7.9 Dimensions

|                                     |  |
|-------------------------------------|--|
| <i>Width</i>                        | 0.28 m   |
| <i>Height</i>                       | 0.73 m   |
| <i>Depth</i>                        | 0.53 m   |
| <i>Weight (without accessories)</i> | 1.855.0010: 15.5 kg<br>1.855.0020: 16.4 kg<br>1.855.0030: 15.5 kg<br>1.855.0040: 16.4 kg |
| <i>Material</i>                     |  |
| <i>Housing</i>                      | Metal housing, surface-treated   |

## 8 Accessories

Up-to-date information on the scope of delivery and optional accessories for your product can be found on the Internet. You can download this information using the article number as follows:

### Downloading the accessories list

- 1** Enter <https://www.metrohm.com/> into your Internet browser.
- 2** Enter the article number (e.g. **855**) into the search field.  
The search result is displayed.
- 3** Click on the product.  
Detailed information regarding the product is shown on various tabs.
- 4** On the **Included parts** tab, click on **Download the PDF**.  
The PDF file with the accessories data is created.



#### NOTICE

Once you have received your new product, we recommend downloading the accessories list from the Internet, printing it out and keeping it together with the manual for reference purposes.



# Index

|                                   |        |
|-----------------------------------|--------|
| 6.2151.000 controller cable ..... | 16     |
| 685 Dosimat plus .....            | 34     |
| 700 Dosino .....                  | 34     |
| 741 Stirrer .....                 | 31     |
| 800 Dosino .....                  | 34     |
| 801 Stirrer .....                 | 35     |
| 802 Stirrer .....                 | 31     |
| 803 Ti Stand .....                | 35     |
| 804 Ti Stand .....                | 35     |
| 805 Dosimat .....                 | 34     |
| <b>A</b>                          |        |
| Aspiration equipment .....        | 24     |
| Axial distance .....              | 18     |
| <b>B</b>                          |        |
| Back panel .....                  | 12     |
| Barcode reader                    |        |
| Connect .....                     | 37     |
| Beaker sensor .....               | 23, 52 |
| <b>C</b>                          |        |
| Computer                          |        |
| Connect .....                     | 16     |
| Connect                           |        |
| Barcode reader .....              | 37     |
| Computer .....                    | 16     |
| Dosing device .....               | 34     |
| MSB devices .....                 | 33     |
| Power grid .....                  | 15     |
| Remote Box .....                  | 36     |
| Stirrer .....                     | 35     |
| Titration stand .....             | 35     |
| USB devices .....                 | 37     |
| Connector                         |        |
| MSB .....                         | 4      |
| USB .....                         | 4      |
| Connectors .....                  | 12     |
| Controller                        |        |
| Connector .....                   | 12     |
| <b>D</b>                          |        |
| Device software                   |        |
| Update .....                      | 2      |
| DIS-COVER .....                   | 54     |
| Distributor .....                 | 26     |
| Dosing device                     |        |
| Connect .....                     | 34     |
| Drip pan .....                    | 40     |
| Drive disk .....                  | 22     |

|  |                |
|--|----------------|
| Driver software                              |                |
| Install .....                                | 16             |
| <b>E</b>                                     |                |
| Electrode                                    |                |
| Mount .....                                  | 30             |
| Electrostatic charge .....                   | 7              |
| <b>F</b>                                     |                |
| Ferrite core                                 |                |
| Mount .....                                  | 34             |
| <b>G</b>                                     |                |
| Guide bolts .....                            | 22             |
| Guide chain .....                            | 27             |
| <b>I</b>                                     |                |
| Install                                      |                |
| Pump .....                                   | 32             |
| Installation                                 |                |
| Driver software .....                        | 16             |
| <b>L</b>                                     |                |
| Left-swinging .....                          | 19             |
| Limitation screw .....                       | 21             |
| Luer lock adapter .....                      | 53             |
| <b>M</b>                                     |                |
| Magnet code .....                            | 14             |
| Magnetic stirrer                             |                |
| Mounting .....                               | 31             |
| Maintenance .....                            | 44             |
| Max. swing angle .....                       | 20             |
| Metrohm Serial Bus MSB, see also "MSB" ..... | 33             |
| Model versions .....                         | 3              |
| Mount  |                |
| Aspiration equipment .....                   | 24             |
| Drip pan .....                               | 40             |
| Rinsing equipment .....                      | 24             |
| MSB  |                |
| Connect devices .....                        | 33             |
| Connector .....                              | 12             |
| MSB connector .....                          | 4              |
| <b>P</b>                                     |                |
| Pins .....                                   | 49             |
| Polytron .....                               | 54             |
| Power connection .....                       | 12, 15, 16     |
| Propeller stirrer .....                      | 31             |
| Pump   |                |
| Install .....                                | 32             |
| <b>R</b>                                     |                |
| Rack .....                                   | 13             |
| Rack code .....                              | 14             |
| Remote                                       |                |
| Input .....                                  | 49             |
| Interface .....                              | 49             |
| Output .....                                 | 49             |
| Remote Box                                   |                |
| Connect .....                                | 36             |
| Pin assignment .....                         | 49             |
| Right-swinging .....                         | 19             |
| Rinsing equipment .....                      | 24             |
| Robotic arm                                  |                |
| Beaker sensor .....                          | 23, 52         |
| Bent .....                                   | 53             |
| Configuration data .....                     | 20, 51, 53, 54 |
| Configuring .....                            | 19             |
| Left-swinging .....                          | 21             |
| Luer lock adapter .....                      | 53             |
| Model versions .....                         | 19, 51         |
| Mount .....                                  | 21             |
| Right-swinging .....                         | 21             |
| Titration head .....                         | 51             |
| Transfer head .....                          | 53             |
| Robotic arms                                 |                |
| Model versions .....                         | 53             |
| Rod stirrer .....                            | 31             |
| <b>S</b>                                     |                |
| Safety instructions .....                    | 6              |
| Sample preparation .....                     | 53             |
| Sample rack .....                            | 13             |
| Serial number .....                          | 12             |
| Service .....                                | 6              |
| Stirrer                                      |                |
| Connect .....                                | 35             |
| Connecting .....                             | 31             |
| Mount .....                                  | 30             |
| Stirring rate .....                          | 50             |
| Supply voltage .....                         | 7              |
| Swing axis .....                             | 20             |
| Swing direction .....                        | 21             |
| Swing Head                                   |                |
| Connect .....                                | 18             |
| Swing offset .....                           | 20             |

Swing radius ..... 20  
**T**  
Titration head ..... 51  
    Equip ..... 28  
Titration stand  
    Connect ..... 35

Tower configuration ..... 18  
Tower stirrer ..... 31  
Transfer head ..... 53  
**U**  
Update  
    Device software ..... 2

USB  
    Connector ..... 12  
USB connector ..... 4  
USB devices  
    Connect ..... 37