



- (51) **International Patent Classification:**
G01N 1/08 (2006.01) **G01N 1/28** (2006.01)
G01N 1/42 (2006.01)
- (21) **International Application Number:**
PCT/US2011/061214
- (22) **International Filing Date:**
17 November 2011 (17.11.2011)
- (25) **Filing Language:** English
- (26) **Publication Language:** English
- (30) **Priority Data:**
61/418,688 1 December 2010 (01.12.2010) US
- (71) **Applicants (for all designated States except US):** **PRESIDENT AND FELLOWS OF HARVARD COLLEGE** [US/US]; 17 Quincy Street, Cambridge, Massachusetts 02138 (US). **CHARLES STARK DRAPER LABORATORY, INC.** [US/US]; 555 Technology Square, Cambridge, Massachusetts 02139 (US).
- (72) **Inventors; and**
- (75) **Inventors/Applicants (for US only):** **LARSON, Dale, N.** [US/US]; c/o Charles Stark Draper Laboratory, Inc, 555 Technology Square, Cambridge, Massachusetts 02139 (US). **BELLIO, Stephen, L.** [US/US]; c/o Charles Stark Draper Laboratory, Inc, 555 Technology Square, Cambridge, Massachusetts 02139 (US). **SLUSARZ, John** [US/US]; c/o President and Fellows of Harvard College, 17 Quincy Street, Cambridge, Massachusetts 02138 (US).
- (74) **Agents:** **WALTERS, N. Chris** et al.; Senniger Powers LLP, 100 North Broadway, 17th Floor, St. Louis, Missouri 63102 (US).
- (81) **Designated States (unless otherwise indicated, for every kind of national protection available):** AE, AG, AL, AM, AO, AT, AU, AZ, BA, BB, BG, BH, BR, BW, BY, BZ, CA, CH, CL, CN, CO, CR, CU, CZ, DE, DK, DM, DO, DZ, EC, EE, EG, ES, FI, GB, GD, GE, GH, GM, GT, HN, HR, HU, ID, IL, IN, IS, JP, KE, KG, KM, KN, KP, KR, KZ, LA, LC, LK, LR, LS, LT, LU, LY, MA, MD, ME, MG, MK, MN, MW, MX, MY, MZ, NA, NG, NI, NO, NZ, OM, PE, PG, PH, PL, PT, QA, RO, RS, RU, RW, SC, SD, SE, SG, SK, SL, SM, ST, SV, SY, TH, TJ, TM, TN, TR, TT, TZ, UA, UG, US, UZ, VC, VN, ZA, ZM, ZW.
- (84) **Designated States (unless otherwise indicated, for every kind of regional protection available):** ARIPO (BW, GH, GM, KE, LR, LS, MW, MZ, NA, RW, SD, SL, SZ, TZ, UG, ZM, ZW), Eurasian (AM, AZ, BY, KG, KZ, MD, RU, TJ, TM), European (AL, AT, BE, BG, CH, CY, CZ, DE, DK, EE, ES, FI, FR, GB, GR, HR, HU, IE, IS, IT, LT, LU, LV, MC, MK, MT, NL, NO, PL, PT, RO, RS, SE, SI, SK, SM, TR), OAPI (BF, BJ, CF, CG, CI, CM, GA, GN, GQ, GW, ML, MR, NE, SN, TD, TG).
- Published:**
— without international search report and to be republished upon receipt of that report (Rule 48.2(g))

(54) **Title:** APPARATUS AND METHODS FOR ALIQUOTTING FROZEN SAMPLES

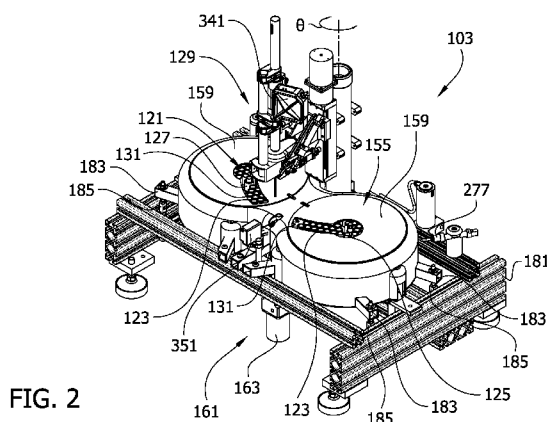


FIG. 2

(57) **Abstract:** A method of obtaining an aliquot of a frozen sample contained in a container includes moving a coring device into the sample and then withdrawing it to obtain a frozen sample core. The location from which the core is taken is selected to be at a radial position where the concentration of at least one substance of interest in the frozen sample core is representative of the overall concentration of that substance in the sample notwithstanding any concentration gradients that may exist in the frozen sample. Another method includes taking two different frozen sample cores from the same sample from radial positions selected such that the concentration of one or more substances of interest in the combined sample cores is representative of the overall concentration of said at least one substance in the sample notwithstanding any radial concentration gradients. A robotic system is programmed or hardwired to implement the methods.

**APPARATUS AND METHODS FOR ALIQUOTTING
FROZEN SAMPLES**

FIELD OF INVENTION

[0001] The present invention relates generally to systems and methods for aliquotting frozen samples, and more particularly to systems and methods for efficiently taking multiple frozen sample cores from a single frozen biological sample to provide a plurality of aliquots that can be analyzed separately without thawing the sample and while minimizing degradation of the sample, protecting the integrity of the sample, and prolonging its usable life.

BACKGROUND

[0002] Biological samples include any samples which are of animal (including human), plant, protozoal, fungal, bacterial, viral, or other biological origin. For example, biological samples include, but are not limited to, organisms and/or biological fluids isolated from or excreted by an organism such as plasma, serum, urine, whole blood, cord blood, other blood-based derivatives, cerebral spinal fluid, mucus (from respiratory tract, cervical), ascites, saliva, amniotic fluid, seminal fluid, tears, sweat, any fluids from plants (including sap); cells (e.g., animal, plant, protozoal, fungal, or bacterial cells, including buffy coat cells; cell lysates, homogenates, or suspensions; microsomes; cellular organelles (e.g., mitochondria); nucleic acids (e.g., RNA, DNA), including chromosomal DNA, mitochondrial DNA, and plasmids (e.g., seed plasmids); small molecule compounds in suspension or solution (e.g. small molecule compounds in DMSO); and other fluid-based biological samples. Biological samples may also include plants, portions of plants (e.g., seeds) and tissues (e.g., muscle, fat, skin, etc.).

[0003] Bio-banks typically cryopreserve these valuable samples (e.g., in freezers at -80 degrees centigrade using liquid Nitrogen or the vapor phase above liquid Nitrogen) to preserve the biochemical composition and integrity of the frozen sample as close as possible to the in vivo state to facilitate accurate, reproducible analyses of the samples.

[0004] From time to time, it may be desirable to run one or more tests on a sample that has been frozen. For example, a researcher may want to perform tests on a set of samples having certain characteristics. A particular sample may contain enough material to support a number of different tests. In order to conserve resources, smaller samples known as aliquots are commonly taken from larger cryopreserved samples for use in one or more tests so the remainder of the cryopreserved sample will be available for one or more different future tests.

[0005] Biobanks have adopted a couple of different ways to address this. One option is to freeze a sample in large volume, thaw it when aliquots are requested and then refreeze any remainder for storage in the cryopreserved state until future aliquots are needed. This option makes efficient use of freezer space; yet this efficiency comes at the cost of sample quality. Repeated freeze/thaw cycles can degrade critical biological molecules (e.g., RNA) and damage biomarkers, either of which could compromise the results of any study using data obtained from the damaged samples.

[0006] Another option is to freeze a sample in large volume, thaw it when an aliquot is requested, subdivide the remainder of the sample to make additional aliquots for future tests and then refreeze these smaller volume aliquots to cryopreserve each aliquot separately until needed for a future test. This approach limits the number of freeze/thaw cycles to which a sample is exposed, but there is added expense associated with labor, the larger volume of freezer space, and a larger

inventory of containers required to maintain the cryopreserved aliquots. Moreover, the aliquots can be degraded or damaged by even a limited number freeze/thaw cycles. Yet another approach is to divide a large volume sample into smaller volume aliquots before freezing. This approach enables the freeze thaw cycles to be limited to only one, yet there are disadvantages associated with costs of labor, freezer space, and container inventory with this approach.

[0007] U.S. pre-grant publication No. 20090019877, the contents of which are hereby incorporated by reference, discloses a system for extracting frozen sample cores from a single frozen biological sample without thawing the sample. The system uses a drill including a hollow bit coring needle to take a frozen core sample from the original sample without thawing the sample. The frozen sample core obtained by the drill is used as the aliquot for the test. After the frozen core is removed, the remainder of the sample is returned to the freezer until another aliquot from the sample is needed for a future test. The present inventors have made various improvements on the system disclosed in the '877 publication, as will be described in detail below.

SUMMARY

[0008] One aspect of the invention is a method of obtaining an aliquot of a frozen sample contained in a container, wherein the sample includes two or more substances. The method includes moving a sample coring device into the frozen sample at a location and then withdrawing the sample coring device from the sample to obtain the aliquot in the form of a frozen sample core taken from that location. The location is selected to be at a radial position where the concentration of at least one substance of interest in the frozen sample core is representative of the overall concentration of said at least

one substance of interest in the sample notwithstanding any concentration gradients that may exist in the frozen sample.

[0009] Another aspect of the invention is a method of obtaining an aliquot of a frozen sample contained in a container, wherein the sample includes two or more substances. The method includes moving a sample coring device into the frozen sample at a first location and then withdrawing the sample coring device from the sample to obtain a first aliquot in the form of a frozen sample core taken from the first location. The sample coring device or another sample coring device is moved into the frozen sample at a second location having a different radial position within the sample from the first location and then withdrawn from the sample to obtain a second aliquot in the form of a frozen sample core taken from the second location. The first and second aliquots are combined to form an aggregate aliquot. The first and second locations are selected so the concentration of at least one substance of interest in the aggregate aliquot is representative of the overall concentration of that substance of interest in the sample notwithstanding any concentration gradients that may exist in the frozen sample.

[0010] Still another aspect of the invention is a system for obtaining frozen aliquots from frozen samples. The system has a platform for supporting a plurality of containers containing the frozen samples. A sample coring device includes a coring bit adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples and then withdrawn from the frozen samples. A robotic system is adapted to produce relative movement between the sample coring device and platform and to operate the sample coring device to take frozen sample cores from the frozen samples. The system has a processor adapted to control the robotic system. The processor is programmed to accept input from a user and operate in one of

multiple different modes in response to the input. The modes differing from one another in one of more of the following parameters:

- (a) a speed at which the robotic system moves the coring bit axially into the frozen samples to obtain the frozen sample cores;
- (b) a force with which the robotic system moves the coring bit axially into the frozen samples to obtain the frozen sample cores;
- (c) a speed at which the robotic system rotates the coring bit to obtain the frozen sample cores;
- (d) a torque applied to the coring bit to obtain the frozen sample cores;
- (e) an amount of an impact force applied to the coring bit as it is moved axially into the frozen samples to obtain the frozen sample cores;
- (f) a position within each of the respective samples from which the frozen sample cores are taken;
- (g) a depth to which the sample coring device is moved into the frozen sample; and
- (h) a size or shape of a drill bit used by the sample coring device to take the frozen sample core.

[0011] Another aspect of the invention is a high precision automated positioning system. The system has a frame and a platform supported by the frame. The platform is adapted to support a plurality of samples. A temperature control block is supported by the frame and operable to at least one of heat and cool samples when they are on the platform. A robot supported by the frame is adapted to pick up samples off the platform, move the samples relative to the platform, and then place the samples down at a different position relative to the platform. The frame supports the temperature control block so the temperature control block is spaced from the platform by a

gap to allow the platform to move relative to the temperature control block without contacting the temperature control block. The frame is connected to the temperature control block by a plurality of flexure mounts adapted to isolate the frame from thermal expansion or contraction of the temperature control block.

[0012] Yet another aspect of the invention is a system for taking frozen aliquots from a plurality of frozen samples. The system includes a frame and an enclosure supported by the frame. A platform is supported by the frame and adapted to support the frozen samples within the enclosure. A temperature control system is adapted to maintain samples on the platform and within the enclosure at a temperature in the range of about 0 degrees centigrade to about -180 degrees centigrade. A robot has an arm adapted to pick up samples off the platform, move the samples relative to the platform, and then place the samples down at a different position relative to the platform. The robot arm is mounted on the frame at a location outside the enclosure. A sample coring device is mounted on the robot arm. The coring device is operable to take frozen sample cores from the frozen samples.

[0013] Another aspect of the invention is a system for obtaining aliquots of frozen samples from a plurality of sample containers and transferring the aliquots to a plurality of aliquot-receiving containers. The system has a platform for supporting the sample containers and the aliquot-receiving containers. The platform includes at least one turntable. A sample coring device is adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples and then withdrawn from the frozen samples. The sample coring device is mounted above the platform on an arm rotatable about a substantially vertical axis and moveable vertically up and down relative to the platform. A first servo-motor is adapted to

drive rotation of the turntable. A second servo-motor is adapted to rotate the arm. A third servo-motor is adapted to move the arm up and down relative to the platform. The system is constructed so the first, second, and third servo-motors provide the only position control for one or more of the following functions that can be carried out by the system:

- (a) moving a container from the platform to a sample coring station;
- (b) moving another container from the platform to an aliquot receiving station spaced from the sample coring station;
- (c) activating and releasing one or more clamping mechanisms to hold and release the containers in fixed positions at the sample coring and aliquot receiving stations;
- (d) removing threaded caps from the containers;
- (e) scanning a beam from a sample inspection device across a surface of the frozen sample to locate any positions in the sample from which sample cores have already been taken;
- (f) moving a sample coring device into the sample container to obtain a frozen sample core;
- (g) transferring the frozen sample core to the aliquot receiving container at the aliquot receiving station;
- (h) screwing the threaded caps back onto the containers;
- (i) moving the containers back from the sample coring and aliquot receiving stations to the platform; and
- (j) moving the sample coring device to a cleaning station for cleaning.

[0014] Still another aspect of the invention is a system for obtaining aliquots of frozen samples. The system has a platform for supporting a plurality of containers containing

frozen samples. A sample coring device comprising a coring bit is adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples and then withdrawn from the frozen samples. A robotic system is adapted to produce relative movement between the sample coring device and platform and operate the sample coring device to take sample cores from the frozen samples. A sample inspection system is adapted to detect one or more locations within a frozen sample from which a frozen sample core has already been taken. The sample inspection system includes a time-of-flight distance sensor adapted to detect a distance between the sensor and a surface of the samples.

[0015] Another aspect of the invention is a system for obtaining aliquots of frozen samples. The system has a platform for supporting a plurality of containers containing frozen samples. A sample coring device having a coring bit is adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples and then withdrawn from the frozen samples. A robotic system is adapted to produce relative movement between the sample coring device and platform and operate the sample coring device to take sample cores from the frozen samples. A sample inspection system is adapted to detect one or more locations within a frozen sample from which a frozen sample core has already been taken. The sample inspection system has an imaging system adapted to image potentially cored surfaces of the samples and a processor programmed to analyze an image corresponding to only a portion of said potentially cored surface for a respective sample and determine whether or not said portion has been cored.

[0016] Still another aspect of the invention is a system for obtaining aliquots of frozen samples. The system has a platform for supporting a plurality of containers containing frozen samples. A sample coring device having a coring bit is

adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples and then withdrawn from the frozen samples. A robotic system is adapted to produce relative movement between the sample coring device and platform and operate the sample coring device to take sample cores from the frozen samples. A sample inspection system is adapted to detect one or more locations within a frozen sample from which a frozen sample core has already been taken. The sample inspection system includes a sensor that is operable to identify whether or not a potentially-cored surface of a sample has been cored at a particular location regardless of whether or not the potentially-cored surface has physical characteristics that cause it to reflect light in a diffuse manner.

[0017] Another aspect of the invention is a system for taking a plurality of aliquots from a plurality of frozen samples. The system has a sample coring device for taking a frozen sample core from a frozen sample. The sample coring device includes a moveable arm and a hollow coring bit mounted on the arm. A cleaning system includes a cleaning station having a housing having a chamber, an opening adapted for receive at least the lower end of the coring bit in the chamber, and a fluid inlet positioned to allow a cleaning fluid to flow into the chamber and contact an exterior of the coring bit. The cleaning system includes a cleaning fluid supply line connected to an inlet on the arm. The inlet on the arm is in fluidic connection with the hollow center of the coring bit for contacting the hollow center of the coring bit with the cleaning fluid.

[0018] Still another aspect of the invention is a system for taking a plurality of aliquots from a plurality of frozen samples. The system includes a sample coring device for taking a frozen sample core from a frozen sample. The sample coring device has a moveable arm and a hollow coring bit mounted on the

arm. A cleaning system includes a cleaning station having a housing having a chamber and an opening adapted for receiving at least the lower end of the coring bit in the chamber. The cleaning system has a cleaning fluid supply and a drying gas supply. The cleaning system is adapted to inject cleaning fluid into the chamber to clean the coring bit and inject drying gas into the chamber to removed residual cleaning fluid from the coring bit by evaporation in the chamber. In some embodiments a plunger is mounted on the arm above the coring bit. The plunger is moveable from a first position in which the plunger is at a relatively higher position relative to the coring bit to a second position in which the plunger is at a relatively lower position relative to the coring bit. The plunger extends into the hollow center of the coring bit in the second position for ejecting a frozen sample core from the coring bit. The inlet on the arm is positioned so cleaning fluid supplied to the arm contacts the exterior of the plunger. The coring bit can be held in a rotatable spindle assembly mounted on the arm. The spindle assembly includes a hollow center in fluid communication with the hollow center of the coring bit. The cleaning system can have a tube on the arm moveable from a first position in which the tube does not contact the spindle assembly and a second position in which the tube forms a seal against the spindle assembly. The inlet on the arm being on the tube. The plunger can extend through the tube and the inlet can be positioned on the tube so cleaning fluid supplied to the arm contacts the exterior of the plunger. The system can include a supply of a drying gas. The cleaning system can be being adapted to cause the drying gas to contact the coring bit after the coring bit has been contacted by the cleaning fluid. For example, the cleaning system can be adapted to inject the drying gas through the inlet on the arm. The cleaning system is adapted to inject

the drying gas into the chamber for receiving the lower portions of the coring bit.

[0019] Other objects and features will in part be apparent and in part pointed out hereinafter.

BRIEF DESCRIPTION OF DRAWINGS

[0020] FIG. 1 is a perspective of one embodiment of an aliquotting system of the present invention;

[0021] FIG. 2 is a perspective of the system with the outer enclosure removed;

[0022] FIG. 3 is an exploded perspective of the system as illustrated in Fig. 2;

[0023] FIG. 4 is an enlarged perspective similar to Fig. 2 but with a robot arm removed and portions of a cover broken away to reveal a platform for supporting sample containers;

[0024] FIG. 5 is a front elevation of the system as illustrated in Fig. 4 with a portion of the cover broken away;

[0025] FIG. 6 is a top plan view of the system as illustrated in Figs. 4 and 5 with a different portion of the cover broken away;

[0026] FIG. 7 is a section of the system taken in a plane including line 7--7 on Fig. 6;

[0027] FIG. 8 is a perspective of the system sectioned as illustrated in Fig. 7 and with the cover removed;

[0028] FIG. 9 is a perspective of the system sectioned in a plane including line 9--9 on Fig. 6;

[0029] FIGS. 10, 10A, 11, and 11A are enlarged sections of a portion of the system taken in a plane including line 10--10 on Fig. 6, illustrating operation of a clamping system for retaining containers;

[0030] FIG. 12 is an enlarged section taken in a plane including line 12--12 on Fig. 6 showing a portion of the frame of the system;

[0031] FIG. 13 is a perspective of the robot arm of the system;

[0032] FIG. 14 is a section of the robotic arm taken in a plane including line 14--14 on Fig. 13;

[0033] FIG. 15 is an exploded perspective of a portion of the robot arm;

[0034] FIGS. 16A and 16B illustrate a sequence in which a plunger in the robot arm ejects a frozen sample core from a coring bit;

[0035] FIGS. 17A-17F illustrate operation of one embodiment of a cleaning system adapted to clean the plunger and coring bit;

[0036] FIGS. 18A and 18B are schematic diagrams illustrating a frozen sample from which multiple frozen sample cores have already been taken being inspected by a sample inspection device;

[0037] FIG. 18C is a graph illustrating the output from a sensor adapted to identify locations within a frozen sample from which aliquots have previously been taken;

[0038] FIG. 18D is a schematic diagram illustrating use of a time-of-flight based distance sensor to inspect a sample;

[0039] FIG. 19 is an enlarged perspective of the tip of the coring bit;

[0040] FIG. 20 is a perspective of a removable tray for holding containers on the system; and

[0041] FIGS. 21 and 22 are perspectives of a toggle mechanism for selectively clamping and releasing containers on a platform of the system.

[0042] Corresponding reference characters indicate corresponding parts throughout the drawings.

DETAILED DESCRIPTION

[0043] Referring now to the drawings, first to Figs. 1 and 2, one embodiment of an automated frozen sample aliquotting system, generally designated 101, includes a robot 103 adapted to automatically take a plurality of frozen aliquots (e.g., in the form of frozen sample cores) from a plurality of different frozen samples. The samples are suitably frozen biological samples.

[0044] Biological samples include any samples which are of animal (including human), plant, protozoal, fungal, bacterial, viral, or other biological origin. For example, biological samples include, but are not limited to, organisms and/or biological fluids isolated from or excreted by an organism -- such as plasma, serum, urine, whole blood, cord blood, other blood-based derivatives, cerebral spinal fluid, mucus (from respiratory tract, cervical), ascites, saliva, amniotic fluid, seminal fluid, tears, sweat, any fluids from plants (including sap), cells (e.g., animal, plant, protozoal, fungal, or bacterial cells, including buffy coat cells; cell lysates, homogenates, or suspensions; microsomes; cellular organelles (e.g., mitochondria); nucleic acids (e.g., RNA, DNA), including chromosomal DNA, mitochondrial DNA, and plasmids (e.g., seed plasmids), small molecule compounds in suspension or solution (e.g. small molecule compounds in DMSO), and other fluid-based biological samples. Biological samples may also include plants, portions of plants (e.g., seeds), and tissues (e.g., muscle, fat, organs, skin, etc.).

[0045] The robot 103 includes or is connected to a processor (not shown), such as a computer, that controls operation of the robot. The robot 103 is positioned in an enclosure 105 which protects the robot and also protects an operator from any sharp objects, aerosols, or spray that might be associated with operation of the robot. In the case of frozen

biological samples, which might contain pathogens (e.g., blood-borne pathogens), the enclosure 105 also limits exposure of the operator to potential pathogens. The ability to limit release of sample materials into the environment can be important when the aliquotting system is used to take aliquots from frozen biological samples or other potentially hazardous materials.

[0046] Various different enclosures can be used within the scope of the invention. For example, the enclosure 105 in Fig. 1 includes a base 107 enclosing a lower chamber 109 in which the base of the robot 103 is contained. As illustrated, the base 107 of the enclosure 105 is supported by a stand 111, e.g., a cart having wheels (not shown), so the robot 103 is supported above the floor at a comfortable working height to facilitate manual loading and unloading of samples and aliquots from the robot and other manual work. The cart 111 also makes it easy to move the robot from one location to another. The base 107 of the enclosure 105 could instead be positioned on a table or work bench. It is also understood the base of the robot 103 does not need to be supported at any particular elevation within the broad scope of the invention.

[0047] The enclosure 105 also includes a removable cover 115 atop the enclosure base 107. The cover 115 can be removed to access the robot 103 for maintenance or repair as may be needed from time to time. The enclosure 105 also includes a door 117 on the front of the cover 115 that can be opened to load and unload the frozen sample vials and frozen aliquot vials from the system and/or perform limited maintenance or repairs on the system 101 without removing the cover. The cover 115 also helps insulate the frozen samples from thermal variables in the room containing the robot 103. It is contemplated that the enclosure 105 can be omitted from the system, such as if the circumstances permit operation without any enclosure or the system is to be placed in a separate fume or biological hood or other device that

sufficiently addresses any concerns about release of materials from the samples into the environment.

[0048] Referring to Figs. 2 and 3, the robot 103 includes a high-precision automated positioning system 121 adapted to move multiple sample-containing and aliquot-receiving containers C (e.g., vials) between temporary storage locations 123 and a sample-coring station 125 or aliquot receiving station 127, respectively. The high precision positioning system 121 facilitates obtaining aliquots in the form of frozen sample cores from precise locations within the sample containers. For example, the positioning system 121 is suitably capable of maintaining actual positioning that is within a few thousandths of an inch (e.g., about 4 thousandths of an inch) of targeted positioning, while conducting operations in a cold environment adapted to minimize undesirable thermally-induced changes to frozen biological samples. This can facilitate taking the frozen sample cores from locations that are selected to optimize the quality of the aliquot (e.g., as will be described in greater detail later) and/or maximizing the number of aliquots that can be taken from a single sample container. Although the ability to maintain precise positioning can be advantageous, it is not necessary within the broad scope of the invention.

[0049] Although it is possible to use an x, y, z, Cartesian coordinate positioning system within the broad scope of the invention, the positioning system 121 in the illustrated embodiment is a θ , θ' , z positioning system. The positioning system 121 suitably includes one or more moveable platforms 131 for supporting the containers and a robotic arm 129 (the details of which will be described later) adapted to pick up samples off the platform(s), move the samples relative to the platform(s), and then place the samples down at a different position relative to the platform(s). As illustrated in Figs. 3-6, for example, the positioning system 121 includes two rotatably-mounted

platforms 131 (e.g., turntables) that support the containers c and a servo-controlled drive system 161 adapted to control movement of the turntables. The turntables 131 suitably support a plurality of receptacles 133 in which the containers C can be received to hold the containers at fixed positions relative to the respective turntable. The sample coring station 125 is suitably a receptacle 133 at the center of one of the turntables 131 and the aliquot receiving station 127 is suitably a receptacle at the center of the other turntable.

[0050] In the illustrated embodiment, the turntables 131 are adapted to support a plurality of removable trays 135, each of which is capable of supporting a plurality of containers C. For example, the upper surfaces of the turntables 131 may include recesses 137 configured to receive the trays 135 and hold them in position on the turntables. Each receptacle 133 in the illustrated embodiment is defined by an upright peripheral (e.g., cylindrical) sidewall supported by one of the trays 135. For example, open-ended cylindrical sleeves 139 can be inserted into wells 141 on the upper surfaces of the trays 135 to form the receptacles 133. Similar sleeves 139 are inserted into wells 143 at the center of the turntables 131 to form receptacles 133 at the sample coring and aliquot receiving stations 125, 127. The sleeves 139 are suitably made of a solid thermally conductive material such as metal and have a relatively high thermal mass so frozen samples or frozen aliquots inside the sleeves are thermally protected by the sleeve.

[0051] Another embodiment of a tray 135' is illustrated in Fig. 20. This tray 135' is a one-piece tray or tray insert in which relatively deep receptacles 133' are formed in a solid one-piece body 137' so the body extends up along the sides of a sample to provide thermal protection for the sample when the sample is received in one of the receptacles.

[0052] The removable trays 135, 135' facilitate loading and unloading containers from the turntables 131 because an entire tray and the containers thereon can be loaded or unloaded together in a single step. Although the receptacles 133, 133' in the illustrated embodiment are circular in shape, it is understood the receptacles could have other shapes including polygonal shapes (e.g., square, hexagonal, etc.) within the scope of the invention. It is also understood that there are various other ways to adapt a platform for supporting a plurality of containers without using any trays or receptacles within the broad scope of the invention.

[0053] The drive system 161 for the turntables 131 suitably includes a single precision motion control device 163 (e.g., servo-motor) adapted to control movement of both turntables 131. As used herein the term "precision motion control device" refers to a mechanical drive system adapted to track a drive output, such as position or velocity, and ensure that a desired drive output is attained. Precision motion control devices include servo-motors and servo-mechanisms, which refer to motors or drive mechanisms having control systems that use feedback to provide precise control (e.g., positional control) of the motor/mechanism and/or one or more structures driven by the device. For example, servo-motors and servo-mechanisms can include control systems that use feedback from one or more position-indicating sensors (not shown) to achieve precise control of the output. The term precision motion control also includes stepper motors, which have motor control systems that track output of the motor by counting the number of steps through which the rotor has been rotated.

[0054] One feature of the system 101 is that it uses a relatively low number of precision motion control devices to perform a large number of varied tasks, as will be described below. Because precision motion control devices are relatively

expensive to build or purchase and because significant maintenance is required to keep a precision motion control device in good working order, the ability to limit the number of precision motion control devices in the system 101 provides advantages. Using a precision motion control device (e.g., a single servo-mechanism 136) to control movement of both turntables is one aspect of this feature of the system 101. Others that may also be present will be described later.

[0055] Referring to Figs. 6-8, the turntable drive motor 163 is mounted under the turntables 131 on a frame 181. The frame 181 also supports the turntables 131 in generally side-by-side relation to one another. For instance, the frame 181 suitably supports a plurality of rollers 197 positioned to engage a radially-outward extending lip 199 on each of the turntables 131 to support the turntables for rotation relative to the frame. The lip 199 is received in a notch (e.g., V-shaped notch) in each of the rollers 197 so the rollers hold the turntable lip at a fixed elevation. As illustrated in Fig. 3, there are three rollers 197 for each turntable 131.

[0056] One or more of the rollers 197 for each turntable is suitably moveable in the radial direction and biased (e.g., by a spring) to move radially inward toward the center of the turntable to ensure the rollers maintain engagement with the turntable lip 199. As illustrated in Fig. 7, for example, the rollers 197 mounted on the far left and right sides of the frame 181 are mounted on a roller support arm 202, which has a generally upright orientation in the illustrated embodiment. The support arm 202 is moveable relative to the frame and biased to move the roller radially inward. In the illustrated embodiment, the support arm 202 is secured to the frame 181 by a bracket 204 that allows pivoting movement of the arm about a pivot axis 206. A spring 208 or other biasing member is positioned to bias the support arm 202 to pivot in the direction in which the roller

moves toward the center of the turntable, as indicated by arrows in Fig. 7. For example, the spring 208 is suitably mounted under the pivot axis 206 and compressed between a side of the support arm 202 and the head of a bolt 210 or other suitable retaining structure fixed to the frame 181. The bolt 210 is suitably adjustable to increase or decrease preload applied to the spring 208. Because one of the rollers 197 for each turntable can move in the radial direction, the rollers 197 are able to accommodate thermal expansion and/or contraction of the turntables 131, while the bias from the preloaded spring 208 ensures the rollers remain snugly engaged with the turntables.

[0057] Referring again to Figs. 6-8, the motor 163 is operably connected (e.g., by a drive shaft 167 as illustrated in Fig. 8) to a wheel 165 so motor is operable to rotate the wheel. The wheel 165 is adjacent the turntables 131 (e.g., generally between the turntables) and is operably connected to each of the turntables 131 so rotation of the wheel by the motor 163 drives rotation of both turntables. For example, the wheel 165 is suitably positioned to simultaneously engage the opposing edges of the turntables 131 so the turntables are rotated at the same time.

[0058] In particular, the wheel 165 in the illustrated embodiment supports a plurality of rotatable pegs 169 and the turntables 131 have teeth 171 that are enmeshed with the pegs so the turntables are turned by the pegs. This results in the turntables 131 being rotated in unison (i.e., at the same time, in the same direction, and at the same speed), but it is understood the turntables are not required to rotate in unison within the broad scope of the invention. The pegs 169 are suitably substantially cylindrical in cross sectional shape and the spaces between the teeth 171 are shaped so they substantially conform to the pegs, as illustrated. The pegs 169 can be made from or include roller bearings, ball bearings, or

other bearings (not shown) that allow the pegs/bearings to rotate relative to the wheel 165 (e.g., on vertical axes when oriented as illustrated) while engaged with either of the turntables 131. The wheel 165 and pegs 169 result in a low-friction, low-backlash, positive drive connection between the motor 163 and the turntables 131, which facilitates very precise positioning of the turntables and the containers C thereon by the positioning system 121.

[0059] The system 101 includes a temperature control system 151 (See Fig. 3) operable to maintain the frozen samples and aliquots at a desired temperature (e.g., at cryogenic temperatures suitably in the range of about 0 degrees centigrade and about -180 degrees centigrade, more suitably in the range of about -40 degrees centigrade and about -180 degrees centigrade, more suitably in the range of about -40 degrees centigrade to about -80 degrees centigrade) while they are on the turntables 131 to limit sample degradation and protect sample and aliquot integrity. It will usually be desirable to operate the temperature control system 151 so the temperature is lower than about -40 degrees centigrade. The temperature control system 151 suitably is programmed to accept input from an operator for setting or adjusting the desired temperature.

[0060] As illustrated, the temperature control system 151 includes a temperature control block 153 positioned under the turntables 131 and an enclosure 155 partially enclosing the temperature control block, along with the turntables 131 and the containers thereon. The enclosure 155 includes a pair of removable covers 159. Each of the turntables 131 is covered by one of the covers 159. Various different temperature control blocks can be used to control the temperature of the frozen samples within the scope of the invention. For example, the temperature control block 153 can include a reservoir or passages (not shown) for containing a cooling fluid, such as

liquid nitrogen or ethanol. By keeping the samples very cold, the temperature control system 151 helps limit (and ideally prevent) melting of the frozen samples during the aliquotting process. The temperature control system 151 also limits frost formation on the frozen samples. It is undesirable for frost to form on the samples because water in the frost can dilute the sample material and thereby alter the results of any quantitative analysis performed on the sample. Although the temperature control system 151 in the illustrated embodiment provides only cooling, it is contemplated that the temperature control system may heat frozen samples within the scope of the invention. For instance, it may be desirable in some cases to warm the frozen samples slightly above their cryogenic storage temperature to make the frozen samples less susceptible to cracking or other physical damage during the aliquotting process.

[0061] The temperature control block 153 is mechanically isolated from the turntables 131 to facilitate highly precise positioning of the sample containers by the positioning system 121. The frame 181 supports the turntables 131 so they are spaced slightly above the temperature control block 153. Accordingly, there are small gaps 157 between the top of the temperature control block 153 and the bottoms of the turntables 131, as illustrated in Figs. 11 and 12. The gaps 157 are suitably no more than about 0.25 inches in length. In general, heat transfer between the temperature control block 153 and the turntables 131 is better when the gaps 157 are relatively small. The gaps 157 are suitably in the range of about 0.0001 inches to about 0.25 inches and more suitably in the range of about 0.001 inches to about 0.006 inches. In the illustrated embodiment, the gaps 157 are equal in length, but this is not required within the broad scope of the invention. Because of the gaps 157 separating the turntables 131 from the temperature control block

153, there is no physical contact between the turntables and the temperature control block. Consequently, the turntables 131 do not slide on, rub against, or otherwise contact the temperature control block 153 as they move. This helps maintain the frozen samples at the desired temperature because there is no heat from friction between the turntables 131 and the temperature control block 153 when the turntables move.

[0062] Although the frame 181 supports the temperature control block 153, the frame is mechanically isolated from the potential effect of thermal expansion and contraction of the temperature control block. This further isolates the turntables 131 (and the positioning system 121 in general) from any thermally-induced strain associated with operation of the temperature control block 153. Referring to Fig. 3, for example, the temperature control block 153 is supported by a plurality of supports 183 (e.g., rectangular bars) connected to the frame 181 by flexure mounts 185. As illustrated in Fig. 12, each flexure mount 185 includes one or more sections 187 adapted to flex generally on an axis 189 generally perpendicular to an imaginary line 191 extending between the connection 193 of the flexure mount to the support 183 and the center 195 of the temperature control block (See Fig. 6). In particular, the flexure mounts 185 are relatively stiff except at the flexible sections 187 and the flexible sections are resistant to bending except along the flexure axis 189. As illustrated in Fig. 12, the flexible sections 187 of flexure mounts include a relatively thin wall 195 or other structure constructed to have a relatively small bending moment about the flexure axis 189 and a relatively higher bending moment in other directions. When the flexure mounts 185 include multiple flexible sections 187, as illustrated, the flexure axes 189 are suitably substantially parallel to one another. Each of the flexure mounts 185 can easily flex at the flexible sections 187 in the directions

indicated by the arrows in Fig. 12 as the temperature control block 153 expands or contracts due to thermal changes to alleviate thermal strain while the flexure mounts collectively support the temperature control block 153 securely below the turntables 131.

[0063] If desired, the temperature control system 151 can also include one or more chillers or other cooling units (not shown) positioned outside the enclosure 155 surrounding the samples to keep the temperature outside the enclosure relatively cool to minimize the temperature difference between the interior and exterior of the enclosure 155. For example, one or more chillers can be used to cool the air or other gas inside the larger enclosure 105 enclosing the robot 103. In some cases, it may be desirable to keep the temperature outside the inner enclosure 155 and inside the outer enclosure 105 at a significantly higher temperature than the temperature inside the inner enclosure. Thus, the temperature control system can be designed to maintain a temperature outside the inner enclosure 155 but inside the outer enclosure 105 above a particular temperature (e.g., above freezing or at about room temperature). This may be desirable, for instance, to avoid the need to operate any precision motion control devices or other components of the system at the low temperatures maintained inside the enclosure 155.

[0064] As illustrated in Figs. 13 and 14, the robot arm 129 is mounted on the frame 181 (e.g., at a location outside the inner enclosure 155) for pivoting movement about a vertical axis 201 as indicated by arrows θ . Rotation of the robot arm 129 on this axis 201 is suitably driven by a precision motion control device. As illustrated, for example, a servo-controlled rotary stage 203 mounted on the frame 181 is adapted to drive rotation of the arm 129 on axis 201. Movement of the robot arm 129 in the vertical Z direction is suitably driven by a precision motion

control device. For example, movement of the robot arm is suitably driven by a servo-controlled linear stage 207 mounted on a support 211 driven by the rotary stage 203. The rotary stage 203 and linear stage 207 are part of the positioning system 121. Accordingly, in the illustrated embodiment the positioning system 121 has no more than three precision motion control devices (e.g., exactly three precision motion control devices).

[0065] The robot arm 129 suitably includes a sample coring device adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples and then withdrawn from the frozen samples. For example, the robot arm 129 in the illustrated embodiment includes a downward extending hollow coring bit 215 (Fig. 19) and a motor 221 (Figs. 14 and 15) operable to rotate the coring bit. For example, the motor 221 is suitably connected to a rotatable spindle assembly 317 holding the coring bit 215 by a belt (Fig. 15). Although the robot arm 129 in the illustrated embodiment is adapted to rotate the coring bit 215, it is understood there are other ways to operate a drill assembly to obtain a frozen sample core within the broad scope of the invention, including the methods disclosed in U.S. pre-grant publication No. 20090019877.

[0066] The motor 221 in the illustrated embodiment is suitably a precision motion control device (e.g., servo-motor) adapted to drive rotation of the coring bit 215. The servo-controlled motor 221, suitably provides very precise control over the speed and torque at which the coring bit is rotated. The ability to control the speed and torque facilitates operation of the coring bit 215 according to various different modes that can be selected to account for the physical characteristics of various types of frozen samples, as will be described in more detail below. Although the coring bit 215 in the embodiment illustrated in the drawings is driven by a

precision motion control device 221, this device is not considered part of the positioning system 121 because it only rotates the coring bit and is not involved in moving the containers C or robot arm 129. In the illustrated embodiment, the entire system 101 includes no more than four (e.g., exactly four) precision motion control devices.

[0067] The robot arm 129 has a pair of gripping mechanisms 251 on opposite sides of the arm. Each gripping mechanism has a gripping arm 253 pivotally mounted on the robot arm 129 and moveable (e.g., by a pneumatic actuator 253) between a retracted position (shown in solid in Fig. 13) and an extended position (shown in phantom in Fig. 13). The arm 253 has one or more movable fingers 257 at its free end. The fingers 257 are selectively moveable (e.g., by another pneumatic actuator 259) between a hold position in which the fingers are relatively closer to one another and a release position in which the fingers are relatively farther from one another. When the arm 253 is in the extended position, the fingers 257 can be moved to selectively grip or release containers C containing frozen samples or frozen aliquots. For example, the gripping mechanisms 251 can be adapted to grip a cap 261 on the top of a container.

[0068] The cap 261 is suitably a threaded cap that can be secured to the container C by screwing the cap onto the top of the container. Thus, when the cap 261 is secured to the container C, the gripping mechanism 251 can pick up the entire container by gripping the cap. The system 101 is also adapted to remove the cap 261 from the container C while it is at the sample coring station 125 or aliquot receiving station 127 without picking up the container. For example, as illustrated in Figs. 10, 10A, 11, 11A, 21, and 22 the system 101 includes a pair of clamping mechanisms 271, each of which is adapted to selectively hold a container C at a respective one of the sample coring and aliquot receiving stations 125, 127 in a fixed

position relative to the respective turntable 131 and release the container to permit the container to be moved relative to the turntable.

[0069] The clamping mechanisms 271 each include a rod 273 extending radially inward toward the sample coring or aliquot receiving station 125, 127 from a toggle mechanism 275 (e.g., mechanical toggle switch) on the perimeter of the respective turntable 131. When the toggle mechanism 275 is in a first position (FIGS. 10, 10A, and 22), the rod 273 extends into the receptacle 133 and clamps the container C in position relative to the turntable 131. When the toggle mechanism 275 is in a second position (Figs. 11, 11A, and 21) the rod 273 does not extend as far toward the center of the turntable 131 as it does in the first position and the rod does not clamp the container C in position. When the container C is not clamped in position by the clamping system 271, the container can easily be rotated relative to the turntable and/or picked up from the turntable 131 (e.g., by the robot arm 129).

[0070] The frame 181 supports a pair of clamping mechanism actuators 277 (e.g., pneumatic actuators) positioned on the periphery of the turntables. The actuators 277 can be extended radially inward to move the toggle mechanism 275 between the first and second positions when the turntable is in an orientation such that the portion of the toggle mechanism to be pushed by the actuator to accomplish the desired movement of the toggle mechanism is aligned with the actuator (see alignment of left turntable 131 to actuator 277 in Fig. 8). The toggle mechanisms 275 are each pushed at one location 279a (Figs. 21 and 22) to clamp the container C and another location 279b to release the container. Thus, in the illustrated embodiment, each turntable 131 is at a first orientation (e.g., as illustrated Fig. 8) when the respective actuator 277 is activated to clamp a container and a second orientation different from the first

(e.g. rotated slightly counterclockwise from the position illustrated in Fig. 8) when the actuator is activated to release the container.

[0071] The robot arm 129 also includes a plunger 231 adapted to eject frozen sample cores from the coring bit 215. As illustrated in Figs. 14-16B, the plunger 231 is suitably mounted above the coring bit 215 and connected to a pneumatic actuator 235 adapted to drive movement of the plunger up and down within the robot arm 129. The plunger 231 is normally in a retracted position (Fig. 16A), in which the bottom of the plunger is spaced above the top of the coring bit 215. After a frozen sample core 241 has been taken from one of the frozen samples, the pneumatic actuator 235 drives the plunger 231 downwardly to an extended position (Fig. 16B) to eject the frozen sample core 241 from the hollow coring bit 215 into an aliquot receiving container C.

[0072] The enclosure 155 for the frozen samples confines the coldest temperatures in the system 101 to relatively small space surrounding the samples. Significantly, the majority of the robot arm 129 remains outside the enclosure 155 even when the robot arm is inserted into the enclosure to drill into a frozen sample or move sample containers. For example, the motors 203, 207 for moving the robot arm 129 and the motor 221 for driving the coring bit 215 are outside the enclosure 155 in an environment that can be warmer than the environment inside the enclosure without degrading frozen samples. The motor 163 for the turntables 131 is also outside the enclosure. Because the motors 203, 207, 221, and 163 are outside the enclosure 155, they do not need to operate at the lower temperatures existing within the enclosure. For example, the motors 203, 207, 221, and 163 can operate at temperatures above freezing, more suitably at temperatures above about 10 degrees centigrade, and still more suitably at temperatures above about 20 degrees centigrade.

[0073] The rollers 197 also are positioned at an outer margin of the enclosure 155. For example, in the illustrated embodiment, the rollers 197 are spaced radially-outward of the temperature control block 153 where the temperature can be warmer than it is in the immediate vicinity of the temperature control block. As illustrated, the rollers 197 are positioned between the turntable and the enclosure 155. Accordingly, the moving parts of the turntable drive system 161 are positioned at the outer margin of the enclosure 155 or outside the enclosure. Accordingly, the rollers 197 and the rest of the turntable drive system 161 can operate at the warmer temperatures existing outside the enclosure 155 or at the margin of the enclosure instead of at the lower temperatures that may exist in the immediate vicinity of the temperature control block 153 and the frozen samples.

[0074] Referring to Figs. 17A-17F, the system 101 includes a cleaning system 281 operable to automatically clean and dry the inside and outside of the coring bit 215 and also clean and dry the lower end of the plunger 231. The cleaning system 281 includes a cleaning station 283 supported by the frame 181. The cleaning station 283 includes a housing 285 having an internal chamber 287 and an opening 289 for inserting the coring bit 215 into the chamber. A drain 291 is installed at the bottom of the chamber 287 and connected to a drain line 293 for draining fluids from the chamber. The housing 285 also has an inlet 295 for receiving one or more cleaning fluids (e.g., a cleaning solution and a rinsing fluid) from a cleaning fluid supply line 297 connected to the housing at the inlet. The cleaning station 238 can optionally include a vibrator (e.g., acoustic or ultrasonic vibrator) (not shown) positioned to agitate cleaning fluid while it is in contact with the coring bit 215 to help dislodge sample materials from the coring bit. For example, the

vibrator can be used to help dislodge proteins or other sticky substances from the coring bit 215.

[0075] The cleaning system 281 also includes a plunger cleaning sub-system 301 on the robot arm 129. The plunger cleaning sub-system 301 includes a plunger seal tube 303 positioned above the motor housing 305. The plunger 231 extends through a hollow center 307 of the plunger seal tube 303. The plunger seal tube 303 has a fluid inlet 311 for receiving one or more cleaning fluids into its hollow center 307 from a fluid supply line 313 connected to the fluid inlet. A sealing member 309 (e.g., an O-ring) at the top of the plunger seal tube 303 seals against the plunger 231 and limits fluid from flow from the hollow center 307 of the plunger seal tube 303 out the plunger seal tube through its top. The plunger seal tube 303 is selectively moveable by an actuator 315 (e.g., a pneumatic actuator) between a position in which the plunger seal tube is spaced slightly above a rotating spindle assembly 317 (Fig. 17C) that holds the coring bit 215 and a position in which the bottom of the plunger seal tube contacts the spindle assembly (Fig. 17D).

[0076] The spindle assembly 317 has a hollow central portion 321 extending from the top of the spindle assembly to the coring bit 215 that is in fluid communication with the hollow center of the coring bit. When the plunger seal tube 303 is moved into contact with the spindle assembly 317, the hollow center 307 of the plunger seal tube is in fluid communication (e.g., aligned with) the hollow central portion 321 of the spindle assembly 317 so fluid in the plunger seal tube can flow down into the spindle assembly and out through the hollow center of the coring bit 215. A sealing member 325 (e.g., an O-ring) forms a seal between the plunger seal tube 303 and the spindle assembly 317 when the plunger seal tube is in contact with the spindle assembly, to limit flow of fluid out of the plunger seal

tube except through the spindle assembly. When the plunger seal tube 303 is in the position in which it does not contact the spindle assembly 317, the spindle assembly can rotate with the coring bit 215 without subjecting the sealing member 325 to any sliding or rubbing.

[0077] To use the cleaning system 281, the robot arm 129 moves the coring bit 215 into alignment with the opening 289 in the top of the cleaning station 283 (see Fig. 17A and 17C). Then the robot arm 129 moves the coring bit 215 down so the lower end of the bit extends into the chamber 287 (see Figs. 17B and 17D). In this position, the bottom of the spindle assembly 317 forms a seal against the housing 285 of the cleaning station. The plunger seal tube actuator 315 moves the plunger seal tube 303 down into contact with the upper portion of the spindle assembly 317 so the sealing member 325 forms a seal between the plunger seal tube and spindle assembly, as illustrated in Fig. 17D.

[0078] To clean the outside of the coring bit 215, cleaning fluid is pumped from a cleaning fluid supply (not shown) through the inlet 295 to inject cleaning fluid into the chamber 287 where it contacts the bit. After contacting the outside of the bit 215, the cleaning fluid exits the chamber through the drain 291. To clean the plunger 231 and inside of the coring bit 215, cleaning fluid is pumped from the same or a different cleaning fluid supply into the robot arm 129 through the plunger seal tube inlet 311 to inject cleaning fluid into the hollow center 307 of the plunger seal tube 303 where it contacts the plunger 231. The cleaning fluid flows from the plunger seal tube 303 into the hollow center 321 of the spindle assembly moving down along the plunger 231, cleaning it as it goes. The cleaning fluid then flows down through the hollow center of the coring bit 215 to clean the inside of the bit. After flowing out of the coring bit 215 into the chamber 287 of the cleaning station, the cleaning fluid is drained through the drain 291. The cleaning

fluid is suitably alternately pumped to the cleaning station 283 to clean the outside of the coring bit 215 and then pumped to the robot arm 129 to clean the plunger 231 and inside of the bit 215. However, if desired cleaning fluid can be pumped to the cleaning station 283 and robot arm 129 concurrently within the scope of the invention. At any time during cleaning, the optional vibrator can be activated to agitate the cleaning fluid to help clean the coring bit 215. In some cases, the cleaning fluid may be clean water or another fluid that does not need to be rinsed off the coring bit 215 or plunger 231. If the cleaning fluid is something other than pure water, the cleaning fluid can be rinsed from the coring bit 215 and plunger 2313 if desired.

[0079] The cleaning system 281 optionally dries the coring bit 215 after cleaning it with the cleaning fluid. A drying gas (e.g., air, nitrogen, or other suitable gas) is suitably pumped from a drying gas supply (not shown) through the same fluid lines as the cleaning to inject drying gas into the chamber of the cleaning station and into the hollow center of the plunger seal tube to dry the inside and outside of the coring bit. When the sample is to be subjected to quantitative analysis it is important to dry the coring bit 215 after cleaning to prevent dilution of the frozen samples with the cleaning fluid. It is understood, however, the cleaning system is not required to dry the coring bit within the broad scope of the invention.

[0080] The system 101 includes a sample inspection system 341 adapted to detect one or more locations within a frozen sample from which a frozen sample core has already been taken. The sample inspection system can include any of a variety of sensors that can be adapted to detect holes in the sample from which frozen cores have already been taken. Suitable sensors and sensor systems that can be used in the sample inspection system 341 include an image analysis system, a vision inspection system, a con-focal imaging system, an optical profilometer, a

time-of-flight distance sensor, an angle of incidence/reflection triangulation based distance sensor, and digital camera, and the like. The foregoing sensors and sensor systems can also be used in any combination to increase robustness of the sample inspection system.

[0081] For instance, one embodiment of a sample inspection system suitably includes a precision triangulation-based optical range finder 341 mounted on the robot arm 129. The range finder 341 is operable to direct a beam 342 of electromagnetic radiation (e.g., an infrared laser beam) onto the upper surface of a frozen sample at the sample coring station 125 (see Fig. 18A). The range finder 341 also includes a detection system 340 to detect electromagnetic radiation 344 reflected from the surface of the sample and determine the spacing between the location 346 where the beam is emitted and the location 348 on the detector 340 where the reflected beam 344 is received by the detector. By rotating the container C (e.g., using the turntable 131) and/or moving the robot arm 129, the entire upper surface of the frozen sample can be scanned by the beam to identify any locations where frozen sample cores have already been taken. For example, Fig. 18B is a graph illustrating how output from the range finder 341 varies as the beam is scanned over the surface of a sample having four frozen sample core holes arranged in a ring at a radius r from the center of the sample by rotating the container C while the robot arm 129 is positioned so the beam is directed onto the sample at location spaced the same distance r from the center as the sample core holes. When the beam scans over a hole, the spacing between the beam emitter and the location where the reflected beam is received changes (as illustrated by the arrows in Fig. 18A). There is a dramatic jump in the output from the range finder when the beam crosses the edge of a hole, allowing the system to determine the presence of a hole.

[0082] Although the triangulation-based optical range finder works well in some cases, the inventors have discovered it does not work well when the physical characteristics of the sample cause it to reflect light in a diffuse manner. Some serum and plasma samples, for example, have characteristics that result in diffuse reflections. When the reflection is diffuse it is difficult or impossible to set the instrument settings so the signal from the sensor can be used to reliably detect any holes in a potentially-cored sample surface. Thus, the sample inspection system desirably includes a sensor that is operable to determine whether or not a potentially-cored surface of the sample has been cored at a particular location regardless of whether or not the sample reflects light in a diffuse manner.

[0083] Another embodiment of the sample inspection system includes a time-of-flight based precision range finder 341' (Fig. 18D). The time-of-flight distance sensor comprises a source of electromagnetic radiation adapted to emit a pulsed beam 342' of electromagnetic radiation (e.g., an infrared laser) onto a surface of the sample and a detector 340' adapted to detect radiation reflected by the surface of the sample. The sensor 341' includes or is connected to a processor adapted to output a signal indicative of a difference in time between the time a pulse in the beam 342' is emitted and the time the detector detects the corresponding pulse in the reflected beam 344'. This time will increase slightly as the beam is scanned over a hole in the surface of the sample, allowing output from the sensor to be used to identify the location of any holes in the surface of the sample.

[0084] Although the time-of-flight sensor described above uses electromagnetic radiation, it is recognized an analogous acoustic based sensor that emits pulsed acoustic signals and detects echoes from the sample surface could be used in a similar manner within the scope of the invention.

[0085] In another embodiment of the system 101, the sample inspection system includes an imaging system (e.g., digital camera not shown) and processor that processes the image to determine if any cores have been taken from a sample. For example, various light/dark contrast algorithms can be used to analyze a complete image of the sample and identify the locations of any holes in the sample surface.

[0086] In still another embodiment of the system 101, the sample inspection system includes a processor programmed to analyze a smaller image of only a portion of the sample surface (or only a portion of a larger image of the entire surface) to make a binary decision (yes/no) about whether there are any holes in the sample that would prevent successful coring of the sample at that particular location. If there are no holes in the area immediate surrounding the potential drilling location, the sample inspection system allows the system to drill at that location. On the other hand, if the sample inspection system detects a hole in the vicinity of the potential drilling location, the robot arm and/or container are moved to assess whether or not a different location is suitable for being the location from which a frozen core is taken for use as an aliquot. The simpler yes/no algorithm is much easier to implement and eliminates the need for more elaborate image processing technology required to simultaneously identify the presence and locations of all holes that may exist in a sample.

[0087] The system 101 optionally includes a bar code reader 351 (e.g., mounted on the frame 181 as illustrated in Fig. 2) for reading bar code labels that may be applied to the containers C to ensure and verify the aliquots are taken from the correct container and placed in the correct container. It is understood a bar code reader could be positioned elsewhere on the system within the scope of the invention.

[0088] To further illustrate the various features of the system 101, one embodiment of a method of using the system to obtain one or more frozen aliquots from frozen samples by taking frozen sample cores will now be described. It is understood that the system 101 can be used in different ways without departing from the scope of the invention.

[0089] To start the process, a plurality of capped containers C containing frozen samples from which one or more aliquots are desired are placed in trays 135 and loaded on one of the turntables 131 (e.g., adjacent the sample coring station 125). A plurality of empty capped containers C for receiving the aliquots are placed in other trays 135 and loaded on one of the turntables 131 (e.g., adjacent the aliquot receiving station 127). For example, all of the frozen sample containers C can suitably be placed on one turntable 131 while all of the aliquot receiving containers are placed on the other turntable. However, it is understood that this is not required to practice the invention.

[0090] After the containers C are loaded on the system 101 the robot 103 begins taking the aliquots. The robot arm 129 moves into a position so one of the gripping mechanisms 251 is above a container C containing a frozen sample. The actuator 255 is activated to move the gripping arm 253 to the extended position. Then the robot arm is lowered until the fingers 257 of the gripping mechanism 251 are adjacent the sides of the cap 261. The finger actuator 259 is activated to move the fingers 257 into contact with opposing sides of the cap to grip the cap. The robot arm 129 is raised to lift the container C, moved to a position so the container is above the sample coring station 125, and then lowered to place the container on the sample coring station.

[0091] Once the container C is received in the receptacle 133 at the sample coring station 125, the turntables 131 are

rotated to align the toggle mechanism actuator 277 with the clamp button 279a on the toggle mechanism 275. The toggle mechanism actuator 277 is extended to push the clamp button 279a on the toggle mechanism and thereby clamp the container at the sample coring station to hold it in a fixed position relative to the turntable 131. While the container C is clamped and the gripping mechanism 251 is still holding the cap, the turntables 131 are rotated to unscrew the cap 261 from the container. The robot arm 129 can be raised as the cap is being unscrewed so the gripping mechanism 251 does not press down on the cap 261 while it is being unscrewed. After the cap 261 is unscrewed, the robot arm 129 is raised further and the gripping arm 253 is retracted by the actuator 255 while still holding the cap.

[0092] The process is repeated using the other gripping mechanism to move the aliquot receiving container to the aliquot receiving station 127 on the other turntable 131. At this point, the sample container C is uncapped and clamped in position at the sample coring station 125 and the aliquot receiving container is uncapped and clamped at the aliquot receiving station 127. The caps 261 for the containers are retained by the retracted gripping mechanism.

[0093] The sample inspection device 241 is used to inspect the upper surface of the frozen sample in the container C at the sample coring station 125 to determine whether any previous frozen sample cores have been taken from the frozen sample. If frozen sample cores have already been taken from the frozen sample, the sample inspection device 341 also determines the locations within the sample from which the frozen cores have been taken, and by a process of elimination identifies one or more positions from which another frozen core can be taken.

[0094] The robot arm 129 moves the coring bit into position above the sample container at the sample coring station 125. In particular, the robot arm 129 moves the bit into a position

above a portion of the sample from which no frozen samples cores have been taken yet. In one example, the location from which the frozen sample core is to be taken is selected to be at a radial position where the concentration of at least one substance of interest in the frozen sample core is representative of the overall concentration of said at least one substance of interest in the sample notwithstanding any concentration gradients that may exist in the frozen sample.

[0095] The present inventors have recognized that radial concentration gradients can develop in a biological sample as it is being frozen. In order to ensure the concentration of the substance of interest in the aliquot is representative of the concentration of that substance in the original unfrozen sample, it may be necessary to take the frozen sample core from a position that is radially offset from the center axis of the sample. The position at which the local concentration in the frozen sample is representative of the overall concentration can vary depending on the characteristics of the sample and the substance of interest and can be determined experimentally for any particular type of sample and substance of interest.

[0096] It is also recognized that two or more frozen sample cores can be taken from different radial positions in the sample that are selected so an aggregate aliquot formed by combining the multiple frozen sample cores has a concentration of a substance of interest that is representative of the concentration of that substance in the original unfrozen sample. For example, a first frozen sample core can be taken from position at which the local concentration of the substance of interest is known to be too high to be representative of the overall sample and a second frozen sample core can be taken from a position at which the local concentration of the substance of interest is too low to be representative of the overall sample. However, the positions from which the first and second sample

cores are taken can be selected so when the first and second sample cores are combined in a single aggregate aliquot the concentration of the substance of interest in the aggregate aliquot is representative of the overall concentration of the substance of interest in the original sample.

[0097] The high-precision positioning system 121 facilitates taking the frozen sample core from the desired location with a high degree of accuracy. This capability can be important when the aliquots are to be used in quantitative tests (i.e., tests in which the concentration or relative concentration of one or more substances is needed). Those skilled in the art will recognize that for some tests, it is only necessary to know whether or not a particular substance is present and the precise concentration at which it is present is not that important. Accordingly, it is not necessary to take the frozen sample core from any particular position within the sample within the broad scope of the invention.

[0098] The coring bit motor 221 turns the coring bit 215 as the robot arm 129 is lowered to move the tip of coring bit 215 from the upper surface of the sample down into the frozen sample. In one embodiment of the method, the coring bit 215 is lowered substantially all the way to the bottom of the container C to obtain a frozen sample core extending substantially all the way through the vertical height of the sample at the location from which the frozen sample core is taken. This can be desirable to account for any vertical concentration gradients that may exist in the sample.

[0099] Once the drilling process is complete, the motor 221 is deactivated to stop rotation of the coring bit 215. Then the robot arm 129 is raised to lift the coring bit and the frozen sample core contained therein out of the sample container. The robot arm 129 is then moved to position the coring bit 125 and the frozen sample core contained therein to a position above the

aliquot receiving container at the aliquot receiving station 127. The plunger actuator 235 is activated to eject the sample core from the coring bit 215 into the aliquot receiving container.

[00100] Once the frozen sample core is in the aliquot receiving container, the robot 103 screws the caps 261 back onto the sample container and the aliquot receiving container using the gripping mechanisms 251 to hold the caps stationary while the turntables 131 are rotated to rotate the clamped containers. The robot arm 129 may move down during the process of screwing the cap 261 back on the containers to track downward movement of the cap as it is screwed on the container. After the caps 261 are back on the containers, the turntables 131 are rotated to align the toggle mechanism actuator 277 with the release buttons 279b on the toggle mechanisms 275. The actuators 277 are extended to press the release buttons 279b and unclamp the containers C so they can be removed from the sample coring and aliquot receiving stations 125, 127. Then the robot arm 129 is moved to position the gripping mechanisms 251 over the containers C to pick them up and move them back to the temporary storage positions 123 on the turntables. In this embodiment of the method, the containers C are only uncapped at the sample coring station 125 or aliquot receiving station 127. The containers C are always capped when they are at any of the storage positions 123.

[00101] If more than one aliquot is needed from the same sample, the process is substantially the same except the robot 103 leaves the sample container C at the sample coring station 125 while it removes the first aliquot receiving container from the aliquot receiving station 127 and replaces it with another aliquot receiving container. Then the robot 103 obtains another frozen sample core from the sample and places it in the second aliquot receiving container. This process can be repeated to

obtain three, four or more aliquots from a single sample during one aliquotting session, as long as there is sufficient sample material for the aliquots. It is also possible to place multiple frozen sample cores into a single aliquot receiving container (e.g., to obtain a larger volume of sample material) within the scope of the invention.

[00102] The cleaning system 281 is then used to clean the coring bit 215 and plunger 231 in the manner described above. After cleaning, the process can be repeated with a different sample. After all the aliquots to be taken from the samples loaded on the system 101 have been taken, the trays 135 are removed from the turntables. The still frozen samples are returned to the cryogenic storage so they will be available in the future if there is a desire to obtain another aliquot for use in a different test. The aliquots are taken from the system 101 and delivered to customers of the biobank or biorepository for testing.

[00103] It will be appreciated from the foregoing that the system 101 is able to accomplish one or more (e.g., all) of the following tasks using only three precision motion control devices (the servo-controlled turntable motor 161, the servo-controlled rotary stage 203 for moving the robot arm 129 in the θ direction, and the servo-controlled linear stage 207 for moving the robot arm in the z-direction) to control positioning of the relevant structures:

- (a) move a container from a temporary storage location 123 to a sample coring station 125;
- (b) move another container from the temporary storage location to an aliquot receiving station 127 spaced from the sample coring station;
- (c) activate and release clamping mechanisms 271 to hold and release the containers in fixed positions at the sample coring and aliquot receiving stations;

- (d) remove threaded caps from the containers;
- (e) scan the beam from the sample inspection device 341 across the upper surface of the frozen sample to locate any positions in the sample from which sample cores have already been taken;
- (f) move a sample coring device (e.g., coring bit 215) into the sample container to obtain a frozen sample core from a location that has not been previously cored;
- (g) transfer the frozen sample core to the aliquot receiving container at the aliquot receiving station;
- (h) screw the threaded caps back onto the containers;
- (i) move the containers back from the sample coring and aliquot receiving stations to the temporary storage location; and
- (j) move the sample coring device to a cleaning station.

[00104] Another feature of the system 101 is the processor is suitably adapted to accept input from a user and operate the system in one of multiple different modes selected by the user. For example, the processor is suitably programmed and/or hardwired to operate in various modes differing from one another in one of more of the following parameters:

- (a) a speed at which the robot 103 moves the coring bit 215 axially into the frozen samples to obtain the sample cores;
- (b) a force with which the robot 103 moves the coring bit 215 axially into the frozen samples to obtain the sample cores;
- (c) a speed at which the robot 103 rotates the coring bit 215 to obtain the sample cores;
- (d) a torque applied to the coring bit to obtain the sample cores;

- (e) an amount of an impact force applied to the coring bit 215 as it is moved axially into the frozen samples to obtain the sample cores;
- (f) a position within each of the respective samples from which the frozen sample cores are taken;
- (g) a depth to which the sample coring device is moved into the frozen sample; and
- (h) a size or shape of a drill bit used by the sample coring device to take the frozen sample core.

[00105] The ability to operate in different modes allows users the flexibility to select a mode designed to facilitate taking frozen sample cores from the frozen samples while limiting the risk and/or extent of physical damage to the sample resulting from the coring process. The variables listed above for the modes can influence the propensity of the frozen sample to crack or otherwise break, be heated by friction, partially melt, or experience other effects that degrade the sample and/or limit the number of frozen sample cores that can be taken from a particular frozen sample. The optimal settings for the variables identified above can vary depending on the characteristics of the frozen sample, the characteristics of the container, the temperature of the frozen samples, and other variables. For example, one mode of operation can be adapted to facilitate taking aliquots from frozen serum sample cores without cracking or otherwise damaging the frozen serum samples and another mode can be adapted to facilitate taking frozen sample cores from frozen plasma samples without cracking or otherwise damaging the frozen plasma samples.

[00106] Having described the invention in detail, it will be apparent that modifications and variations are possible without departing from the scope of the invention defined in the appended claims.

[00107] When introducing elements of the present invention or the preferred embodiment(s) thereof, the articles "a", "an", "the", and "said" are intended to mean that there are one or more of the elements. The terms "comprising", "including", and "having" are intended to be inclusive and mean that there may be additional elements other than the listed elements.

[00108] As various changes could be made in the above constructions, products, and methods without departing from the scope of the invention, it is intended that all matter contained in the above description and shown in the accompanying drawings shall be interpreted as illustrative and not in a limiting sense.

CLAIMS

What is claimed is:

1. A method of obtaining an aliquot of a frozen sample contained in a container, the sample being a mixture comprising two or more substances, the method comprising:

5 moving a sample coring device into the frozen sample at a location and then withdrawing the sample coring device from the sample to obtain the aliquot in the form of a frozen sample core taken from said location,

10 wherein the location is selected to be at a radial position where the concentration of at least one substance of interest in the frozen sample core is representative of the overall concentration of said at least one substance of interest in the sample notwithstanding any concentration gradients that may exist in the frozen sample.

2. A method as set forth in claim 1 wherein said location is offset radially from a geometric center of the sample.

3. A method as set forth in any one of claims 1 and 2 wherein moving the sample coring device into the frozen sample comprises moving the sample coring device substantially all the way from one side of the sample to an opposite side of the
5 sample at said location.

4. A method as set forth in any one of claims 1-3 wherein the sample comprises a substance selected from the group consisting of plasma, serum, urine, whole blood, cord blood, other blood-based derivatives, cerebral spinal fluid, mucus,
5 ascites, saliva, amniotic fluid, seminal fluid, tears, sweat, sap or other plant-derived fluid, animal cells, plant cells, protozoal cells, fungal cells, bacterial cells, buffy coat cells, cell lysates, cell homogenates, cell suspensions,

microsomes, cellular organelles, nucleic acids, small molecule
10 compounds in suspension or solution.

5. A method as set forth in claim 4 wherein the sample comprises a substance selected from the group consisting of serum and plasma.

6. A method as set forth in any one of claims 1-5 further comprising using a sample inspection system to identify whether or not any frozen sample cores have already been taken from the sample, said location being selected to be at a position where
5 no frozen sample cores have previously been taken from the sample.

7. A robotic system programmed or hardwired to implement the method set forth in any one of claims 1-6.

8. A method of obtaining an aliquot of a frozen sample contained in a container, the sample being a mixture comprising two or more substances, the method comprising:

moving a sample coring device into the frozen sample at a
5 first location and then withdrawing the sample coring device from the sample to obtain a first aliquot in the form of a frozen sample core taken from said first location,

moving the sample coring device or another sample coring device into the frozen sample at a second location having a
10 different radial position within the sample from the first location and then withdrawing the sample coring device from the sample to obtain a second aliquot in the form of a frozen sample core taken from said second location, and

combining the first and second aliquots to form an
15 aggregate aliquot,

wherein the first and second locations are selected so the concentration of at least one substance of interest in the aggregate aliquot is representative of the overall concentration

of said at least one substance of interest in the sample
20 notwithstanding any concentration gradients that may exist in
the frozen sample.

9. A system for obtaining frozen aliquots from frozen
samples, the system comprising:

a platform for supporting a plurality of containers
containing the frozen samples;

5 a sample coring device comprising a coring bit adapted to
take frozen sample cores from the frozen samples by being moved
into the frozen samples and then withdrawn from the frozen
samples;

a robotic system adapted to produce relative movement
10 between the sample coring device and platform and operate the
sample coring device to take frozen sample cores from the frozen
samples; and

a processor adapted to control the robotic system, the
processor being programmed to accept input from a user and
15 operate in one of multiple different modes in response to the
input, the modes differing from one another in one of more of
the following parameters:

(a) a speed at which the robotic system moves the coring
bit axially into the frozen samples to obtain the frozen sample
20 cores;

(b) a force with which the robotic system moves the coring
bit axially into the frozen samples to obtain the frozen sample
cores;

(c) a speed at which the robotic system rotates the coring
25 bit to obtain the frozen sample cores;

(d) a torque applied to the coring bit to obtain the
frozen sample cores;

(e) an amount of an impact force applied to the coring bit
as it is moved axially into the frozen samples to obtain the
30 frozen sample cores;

(f) a position within each of the respective samples from which the frozen sample cores are taken;

(g) a depth to which the sample coring device is moved into the frozen sample; and

35 (h) a size or shape of a drill bit used by the sample coring device to take the frozen sample core.

10. A system as set forth in claim 9 wherein the samples include biological materials.

11. A system as set forth in any one of claims 9 and 10 wherein at least one of the modes is adapted to facilitate taking aliquots from frozen samples selected from the group consisting of serum and plasma without cracking or otherwise
5 damaging the frozen samples.

12. A system as set forth in any one of claims 9 and 10 wherein at least one of the modes is adapted to facilitate taking aliquots from frozen samples selected from the group consisting of serum, plasma, cells, urine, solid tissue,
5 cerebral spinal fluid, and combinations thereof.

13. A system as set forth in any one of claims 9 and 10 wherein at least one of the modes is adapted to facilitate taking aliquots from frozen samples comprising at least one of serum and plasma with minimal degradation of the samples.

14. A system as set forth in any of claims 9-13, wherein the modes differ from one another in a speed at which the robotic system moves the coring bit axially into the frozen samples to obtain the frozen sample cores.

15. A system as set forth in any of claims 9-14, wherein the modes differ from one another in a force with which the robotic system moves the coring bit axially into the frozen samples to obtain the frozen sample cores.

16. A system as set forth in any of claims 9-15, wherein the modes differ from one another in a speed at which the robotic system rotates the coring bit to obtain the frozen sample cores.

17. A system as set forth in any of claims 9-16, wherein the modes differ from one another in a torque applied to the coring bit to obtain the frozen sample cores.

18. A system as set forth in any of claims 9-17, wherein the modes differ from one another in an amount of an impact force applied to the coring bit as it is moved axially into the frozen samples to obtain the frozen sample cores.

19. A system as set forth in any of claims 9-18, wherein the modes differ from one another in a position within each of the respective samples from which the frozen sample cores are taken.

20. A system as set forth in any of claims 9-19, wherein the modes differ from one another in a depth to which the sample coring device is moved into the frozen sample.

21. A system as set forth in any of claims 9-20, wherein the modes differ from one another in a size or shape of a drill bit used by the sample coring device to take the frozen sample core.

22. A high precision automated positioning system, the system comprising:

a frame;

a platform supported by the frame and adapted to support a plurality of samples;

a temperature control block supported by the frame and operable to at least one of heat and cool samples when they are on the platform;

10 a robot supported by the frame and adapted to pick up
samples off the platform, move the samples relative to the
platform, and then place the samples down at a different
position relative to the platform,

15 wherein the frame supports the temperature control block so
the temperature control block is spaced from the platform by a
gap to allow the platform to move relative to the temperature
control block without contacting the temperature control block,
the frame being connected to the temperature control block by a
plurality of flexure mounts adapted to isolate the frame from
thermal expansion or contraction of the temperature control
20 block.

23. A system as set forth in claim 21 wherein the platform
comprises a turntable mounted for rotation relative to the
frame.

24. A system as set forth in claim 22 further comprising a
second turntable mounted for rotation relative to the frame,
wherein each of the turntables is mechanically isolated from
thermal expansion and contraction of the temperature control
5 block by the flexure mounts.

25. A system as set forth in any one of claims 21-23
wherein the flexure mounts each comprise a relatively flexible
segment adapted for bending along a bending axis, the bending
axes being oriented so the flexure mount moves in a radial
5 direction toward or away from a center of the temperature
control block as the flexure mounts bend on the axes.

26. A system as set forth in claim 24 wherein the bending
axes for each flexure mount is in a different orientation.

27. A system as set forth in any one of claims 24 and 25
wherein the flexible segment is a first flexible segment and
each flexure mount further comprises a second flexible segment

adapted for bending about a bending axis that is substantially
5 parallel to the bending axis of the first flexible segment.

28. A system for taking frozen aliquots from a plurality of frozen samples, the system comprising:

a frame;

an enclosure supported by the frame;

5 a platform supported by the frame and adapted to support the frozen samples within the enclosure;

a temperature control system adapted to maintain samples on the platform and within the enclosure at a temperature in the range of about 0 degrees centigrade to about -180 degrees
10 centigrade;

a robot having an arm adapted to pick up samples off the platform, move the samples relative to the platform, and then place the samples down at a different position relative to the platform, the robot arm being mounted on the frame at a location
15 outside the enclosure; and

a sample coring device mounted on the robot arm, the coring device being operable to take frozen sample cores from the frozen samples.

29. A system as set forth in claim 27 further comprising a plurality of rollers supported by the frame and a turntable rotatably-supported by the rollers for rotation relative to the frame, wherein the platform is on the turntable and the rollers
5 are positioned at an outer margin of the enclosure.

30. A system as set forth in any one of claims 27 and 28 further comprising a motor adapted to drive rotation of the platform, the motor being positioned outside the enclosure.

31. A system as set forth in any one of claims 28 and 29 wherein the temperature control system comprises a temperature

control block under the turntable, the rollers being spaced radially outward of the temperature control block.

32. A system as set forth in any one of claims 28-30 wherein the rollers are positioned between the turntable and the enclosure.

33. A system as set forth in any one of claims 27-31 wherein the temperature control system is adapted to maintain samples on the platform and within the enclosure at a temperature in the range of about -40 degrees centigrade to
5 about -180 degrees centigrade.

34. A system as set forth in claim 32 wherein the temperature control system is selectively adjustable to vary the temperature at which the frozen samples are maintained.

35. A system for obtaining aliquots of frozen samples from a plurality of sample containers and transferring the aliquots to a plurality of aliquot-receiving containers, the system comprising:

5 a platform for supporting the sample containers and the aliquot-receiving containers, the platform including at least one turntable;

a sample coring device adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples
10 and then withdrawn from the frozen samples, the sample coring device being mounted above the platform on an arm rotatable about a substantially vertical axis and moveable vertically up and down relative to the platform;

a first servo-motor adapted to drive rotation of the
15 turntable;

a second servo-motor adapted to rotate the arm; and

a third servo-motor adapted to move the arm up and down relative to the platform,

wherein the system is constructed so the first, second, and
20 third servo-motors provide the only position control for one or
more of the following functions that can be carried out by the
system:

(a) moving a container from the platform to a sample
coring station;

25 (b) moving another container from the platform to an
aliquot receiving station spaced from the sample coring station;

(c) activating and releasing one or more clamping
mechanisms to hold and release the containers in fixed positions
at the sample coring and aliquot receiving stations;

30 (d) removing threaded caps from the containers;

(e) scanning a beam from a sample inspection device across
a surface of the frozen sample to locate any positions in the
sample from which sample cores have already been taken;

(f) moving a sample coring device into the sample container
35 to obtain a frozen sample core;

(g) transferring the frozen sample core to the aliquot
receiving container at the aliquot receiving station;

(h) screwing the threaded caps back onto the containers;

(i) moving the containers back from the sample coring and
40 aliquot receiving stations to the platform; and

(j) moving the sample coring device to a cleaning station
for cleaning.

36. A system as set forth in claim 34 wherein the platform
comprises first and second turntables and the first servo-motor
is adapted to drive rotation of the first and second turntables.

37. A system as set forth in claim 34 further comprising a
clamping system operable to clamp the container in position at
one of the sample coring and aliquot receiving stations, the
clamping mechanism including a toggle mechanism mounted on the
5 turntable and a toggle mechanism actuator mounted adjacent the

turntable so the first servo-motor can be used to accurately position the toggle mechanism at a location where it can be operated by the toggle mechanism actuator.

38. A system as set forth in claim 36 further comprising a gripping mechanism mounted on the arm, the gripping mechanism being adapted to hold a threaded container cap while the turntable is rotated to rotate a container at said one of the sample coring and aliquot receiving stations.

39. A system as set forth in any one of claims 34-37 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for moving the container from the platform to the sample coring station.

40. A system as set forth in any one of claims 34-38 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for moving said container from the platform to the aliquot receiving station.

41. A system as set forth in any one of claims 34-39 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for activating and releasing said one or more clamping mechanisms to hold and release the containers in fixed positions at the sample coring and aliquot receiving stations.

42. A system as set forth in any one of claims 34-40 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for removing threaded caps from the containers.

43. A system as set forth in any one of claims 34-41 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for scanning a beam from a sample inspection device across a surface

5 of the frozen sample to locate any positions in the sample from which frozen sample cores have already been taken.

44. A system as set forth in any one of claims 34-42 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for moving a sample coring device into the sample container to obtain a
5 frozen sample core.

45. A system as set forth in any one of claims 34-43 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for transferring the frozen sample core to the aliquot receiving
5 container at the aliquot receiving station.

46. A system as set forth in any one of claims 34-44 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for screwing the threaded caps back onto the containers.

47. A system as set forth in any one of claims 34-45 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for moving the containers back from the sample coring and aliquot receiving
5 stations to the platform.

48. A system as set forth in any one of claims 34-46 wherein the system is constructed so the first, second, and third servo-motors provide the only position control for moving the sample coring device to a cleaning station for cleaning.

49. A system as set forth in claim 34 wherein the system is operable to carry out all the functions listed in paragraphs (a)-(j).

50. A system for obtaining aliquots of frozen samples, the system comprising:

a platform for supporting a plurality of containers containing frozen samples;

5 a sample coring device comprising a coring bit adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples and then withdrawn from the frozen samples;

10 a robotic system adapted to produce relative movement between the sample coring device and platform and operate the sample coring device to take sample cores from the frozen samples; and

15 a sample inspection system adapted to detect one or more locations within a frozen sample from which a frozen sample core has already been taken,

wherein the sample inspection system comprises a time-of-flight distance sensor adapted to detect a distance between the sensor and a surface of the samples.

51. A system as set forth in claim 49 wherein the time-of-flight sensor comprises a source of electromagnetic radiation adapted to emit a beam of electromagnetic radiation onto a surface of the sample, a detector adapted to detect
5 electromagnetic radiation reflected by the surface of the sample, and a processor adapted to output a signal indicative of a difference in time between the time when the source emits the beam and the time the detector detects the reflected electromagnetic radiation.

52. A system as set forth in claim 49 wherein the time-of-flight sensor comprise an acoustic signal source of adapted to emit an acoustic signal, a detector adapted to detect an echo of the acoustic signal reflected by a surface of the sample, and a
5 processor adapted to output a signal indicative of the difference in time between the time when the acoustic signal is emitted and the time the echo is detected.

53. A system for obtaining aliquots of frozen samples, the system comprising:

a platform for supporting a plurality of containers containing frozen samples;

5 a sample coring device comprising a coring bit adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples and then withdrawn from the frozen samples;

10 a robotic system adapted to produce relative movement between the sample coring device and platform and operate the sample coring device to take sample cores from the frozen samples; and

15 a sample inspection system adapted to detect one or more locations within a frozen sample from which a frozen sample core has already been taken,

wherein the sample inspection system comprises an imaging system adapted to image potentially cored surfaces of the samples and a processor programmed to analyze an image corresponding to only a portion of said potentially cored surface for a respective sample and determine whether or not
20 said portion has been cored.

54. A system for obtaining aliquots of frozen samples, the system comprising:

a platform for supporting a plurality of containers containing frozen samples;

5 a sample coring device comprising a coring bit adapted to take frozen sample cores from the frozen samples by being moved into the frozen samples and then withdrawn from the frozen samples;

10 a robotic system adapted to produce relative movement between the sample coring device and platform and operate the

sample coring device to take sample cores from the frozen samples; and

15 a sample inspection system adapted to detect one or more locations within a frozen sample from which a frozen sample core has already been taken,

wherein the sample inspection system comprises a sensor that is operable to identify whether or not a potentially-cored surface of a sample has been cored at a particular location regardless of whether or not the potentially-cored surface has
20 physical characteristics that cause it to reflect light in a diffuse manner.

55. A system as set forth in claim 53 wherein the sample inspection system comprises a sensor selected from the group consisting of an image analysis system, a vision inspection system, a confocal imaging system, an optical profilometer, a
5 time-of-flight distance sensor, a digital camera, and combinations thereof.

56. A system as set forth in claim 53 wherein the sample system comprises an optical displacement sensor adapted to detect one or more holes in upper surfaces of the frozen samples.

57. A system as set forth in any one of claims 49-55 wherein the robotic system comprises an arm supporting the sample coring device and the sample inspection system is mounted on the arm.

1/33

FIG. 1

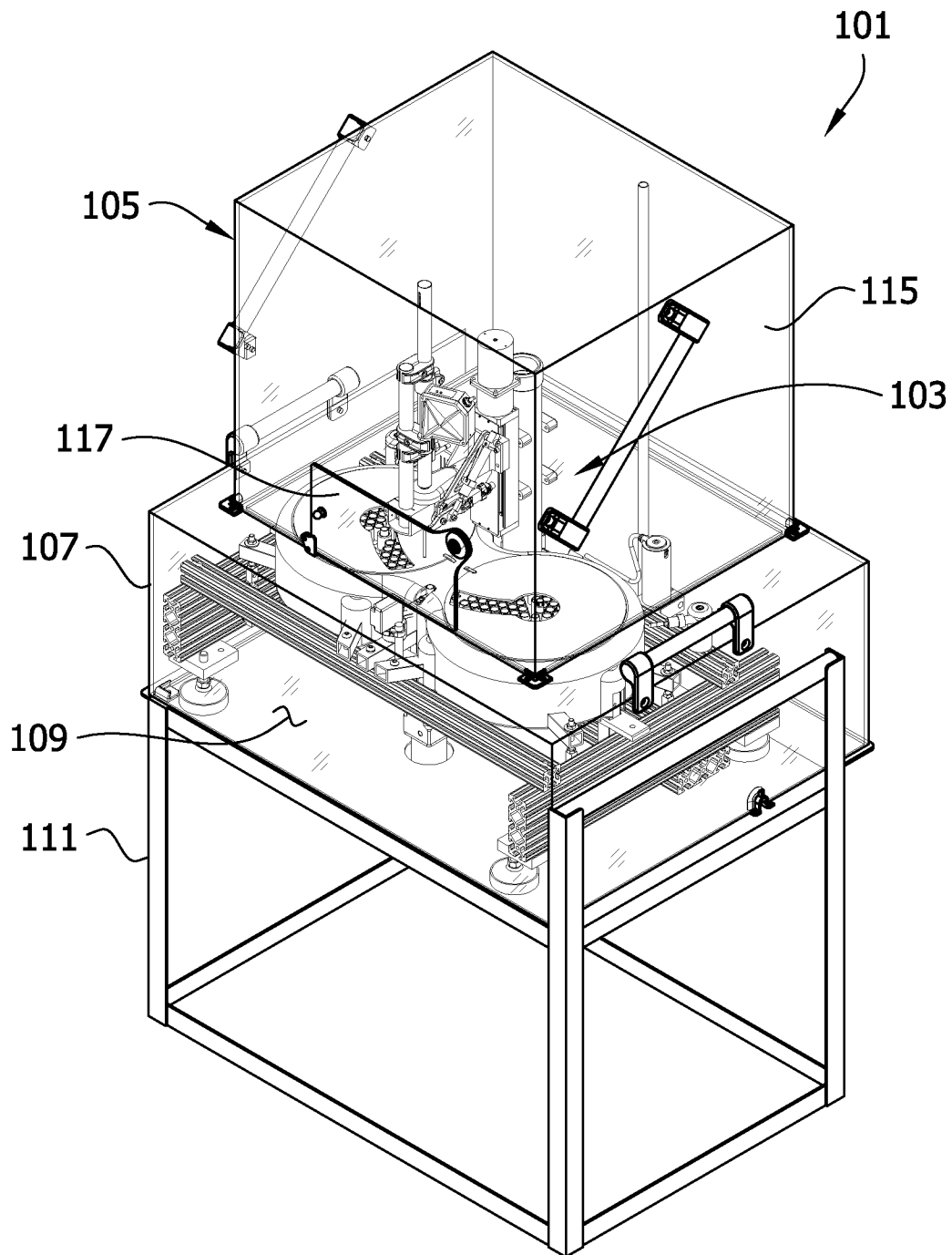


FIG. 2

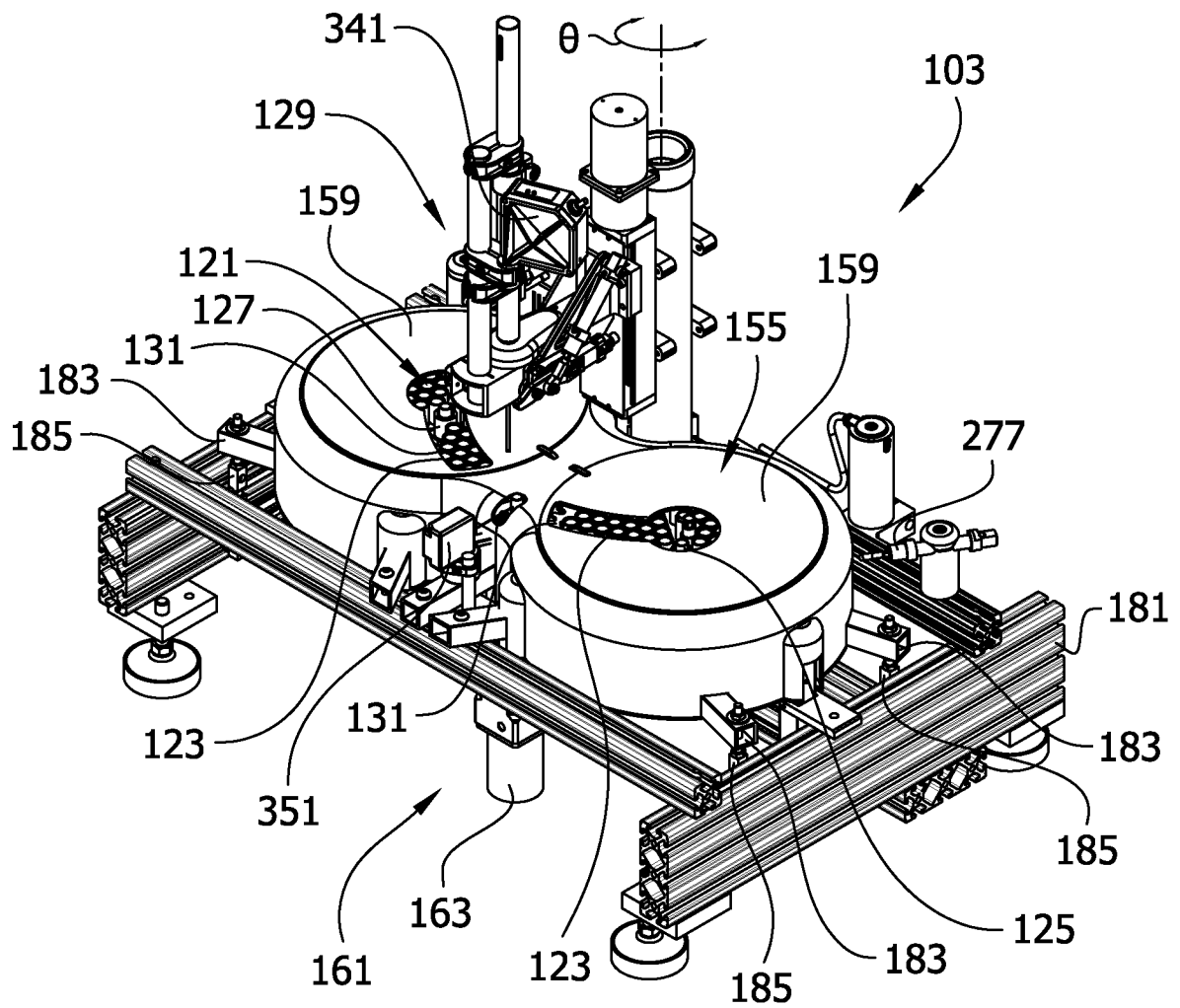
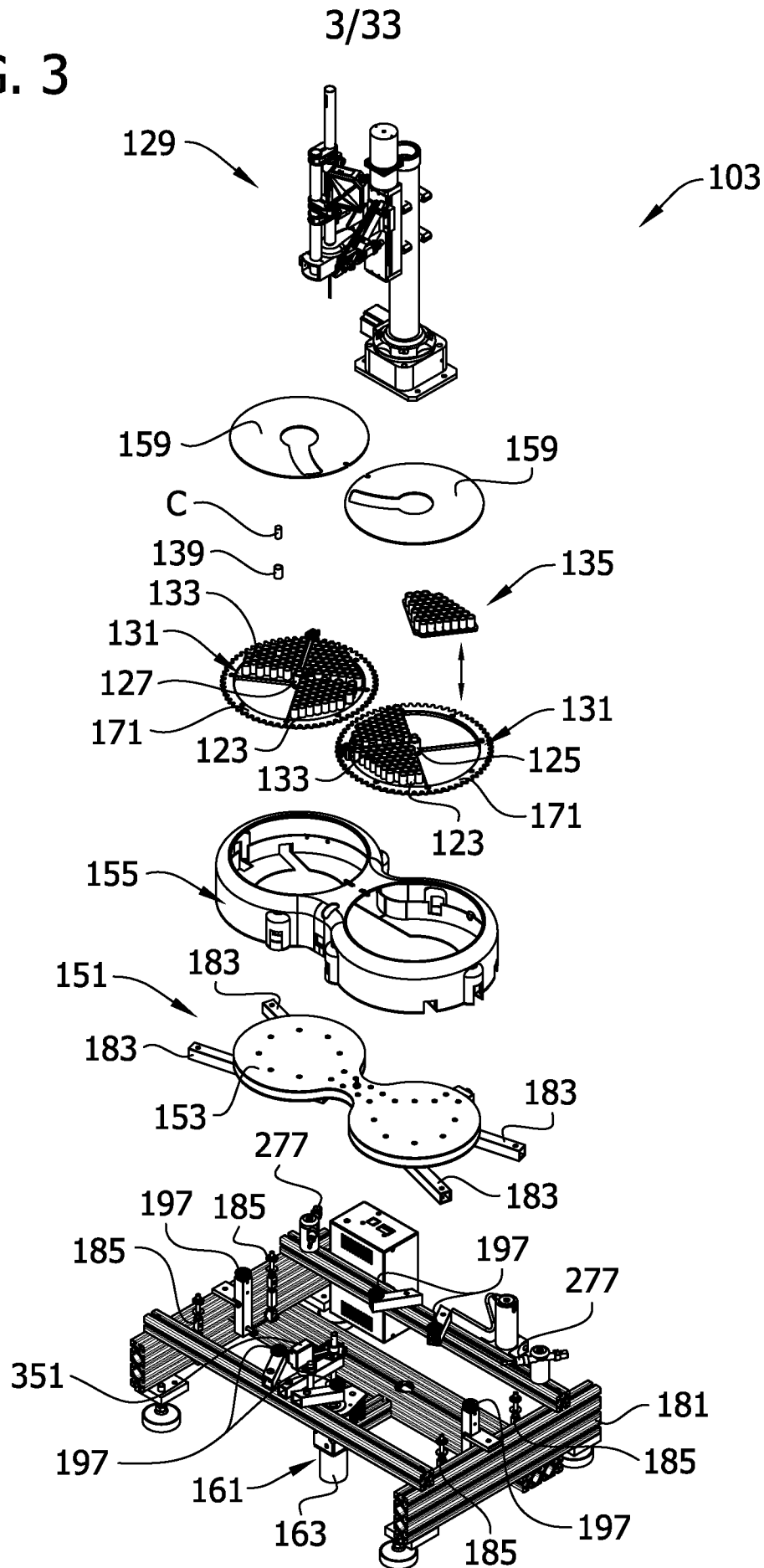


FIG. 3



4/33

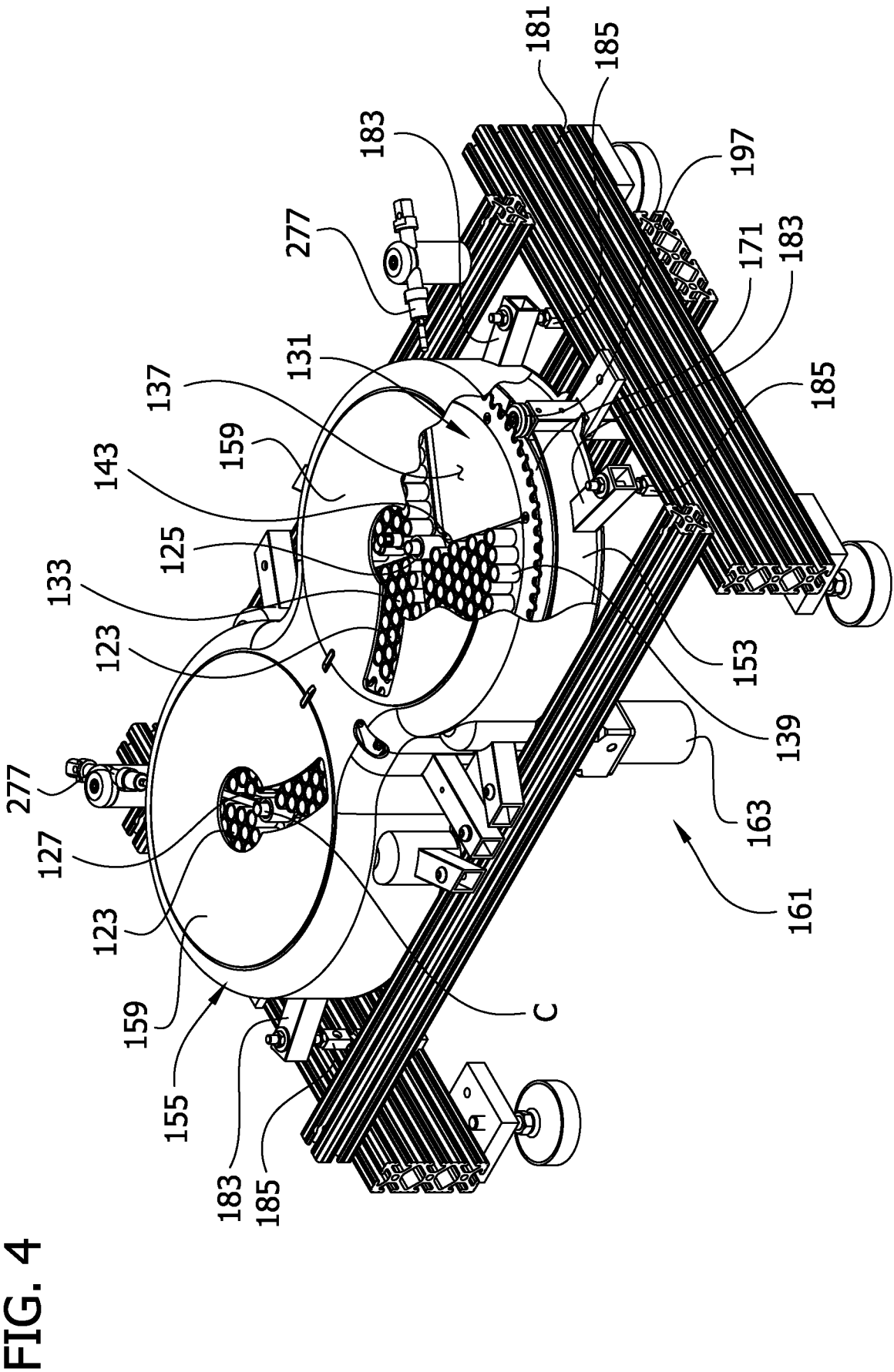
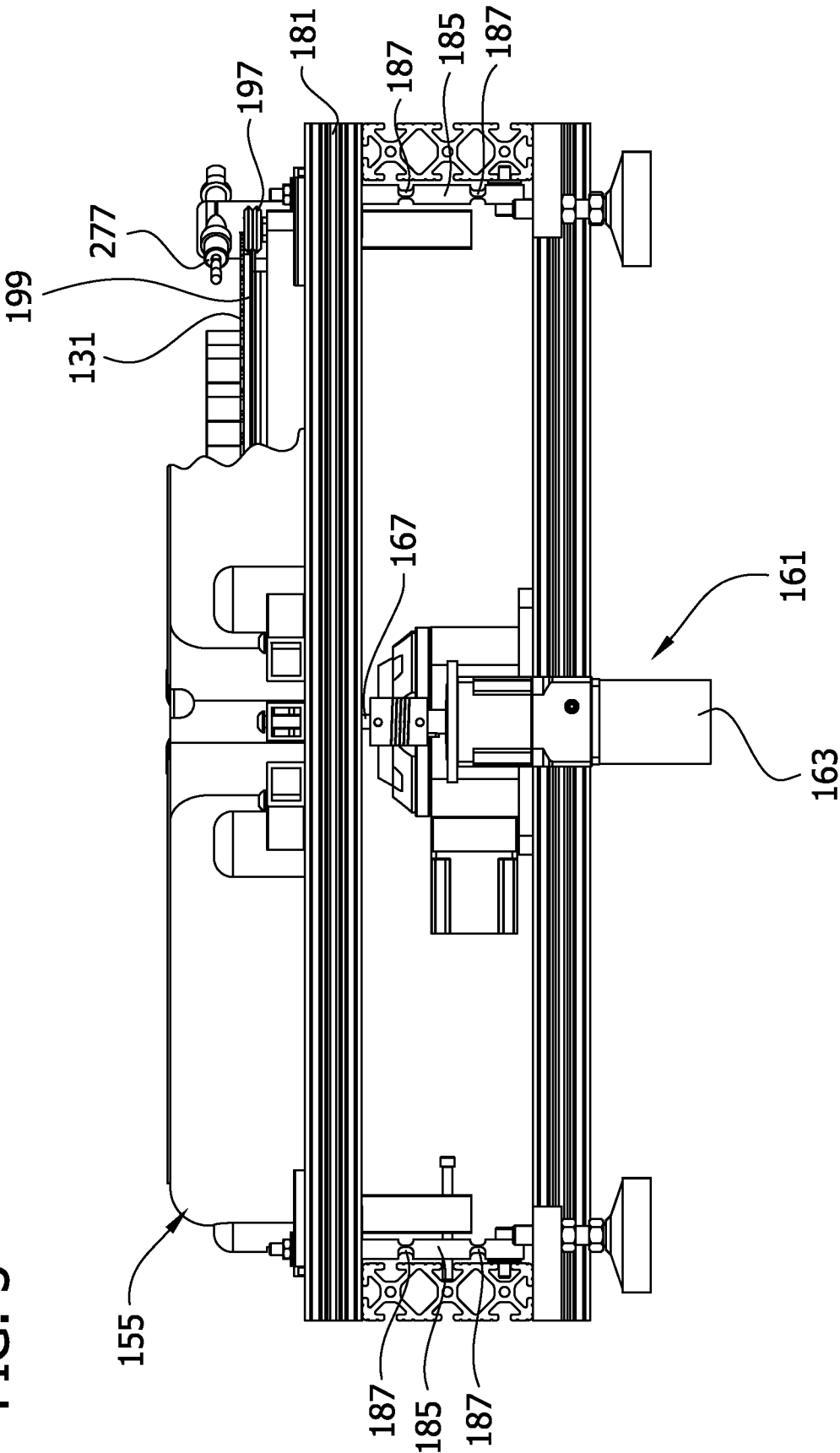


FIG. 5



6/33

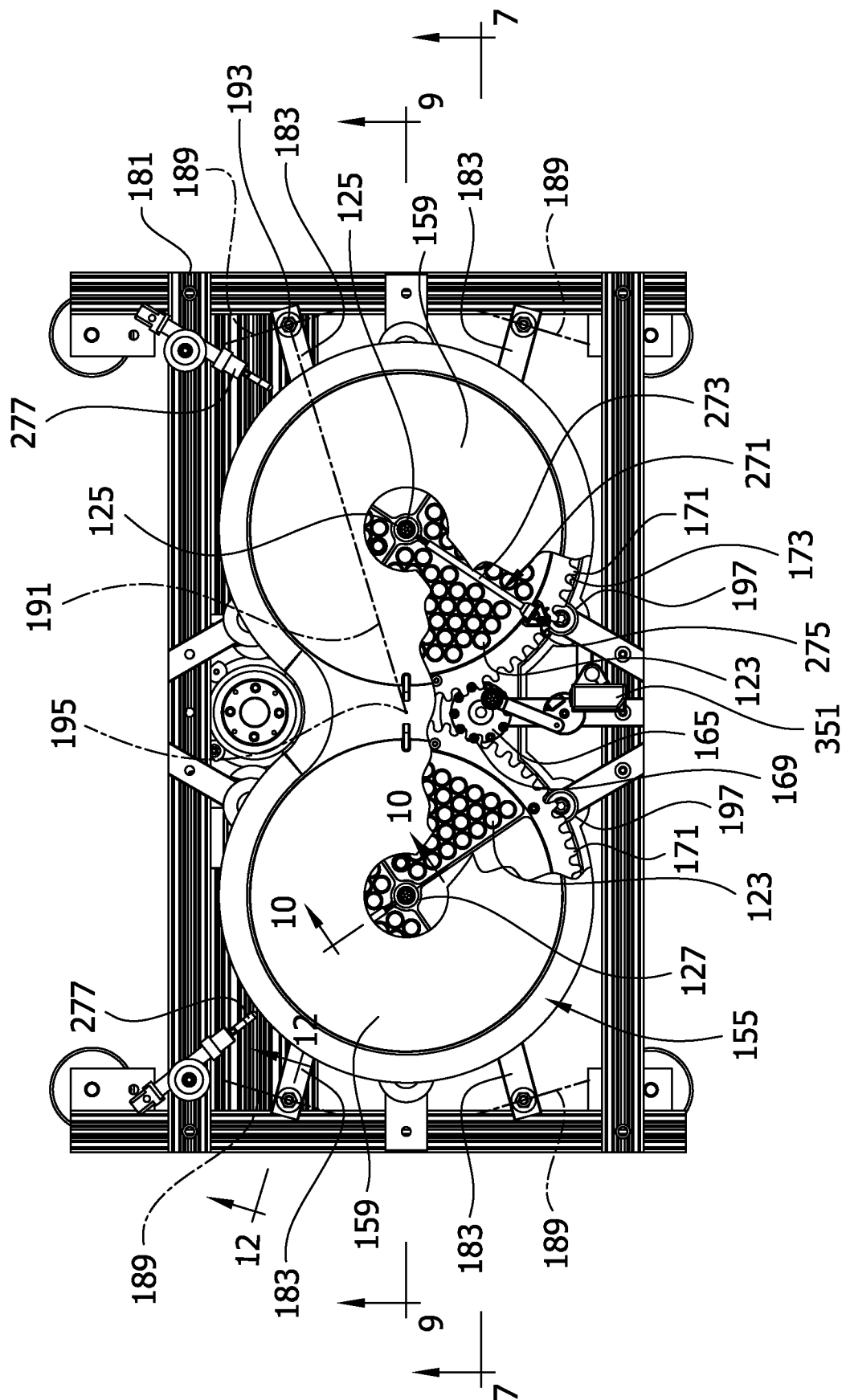


FIG. 6

7/33

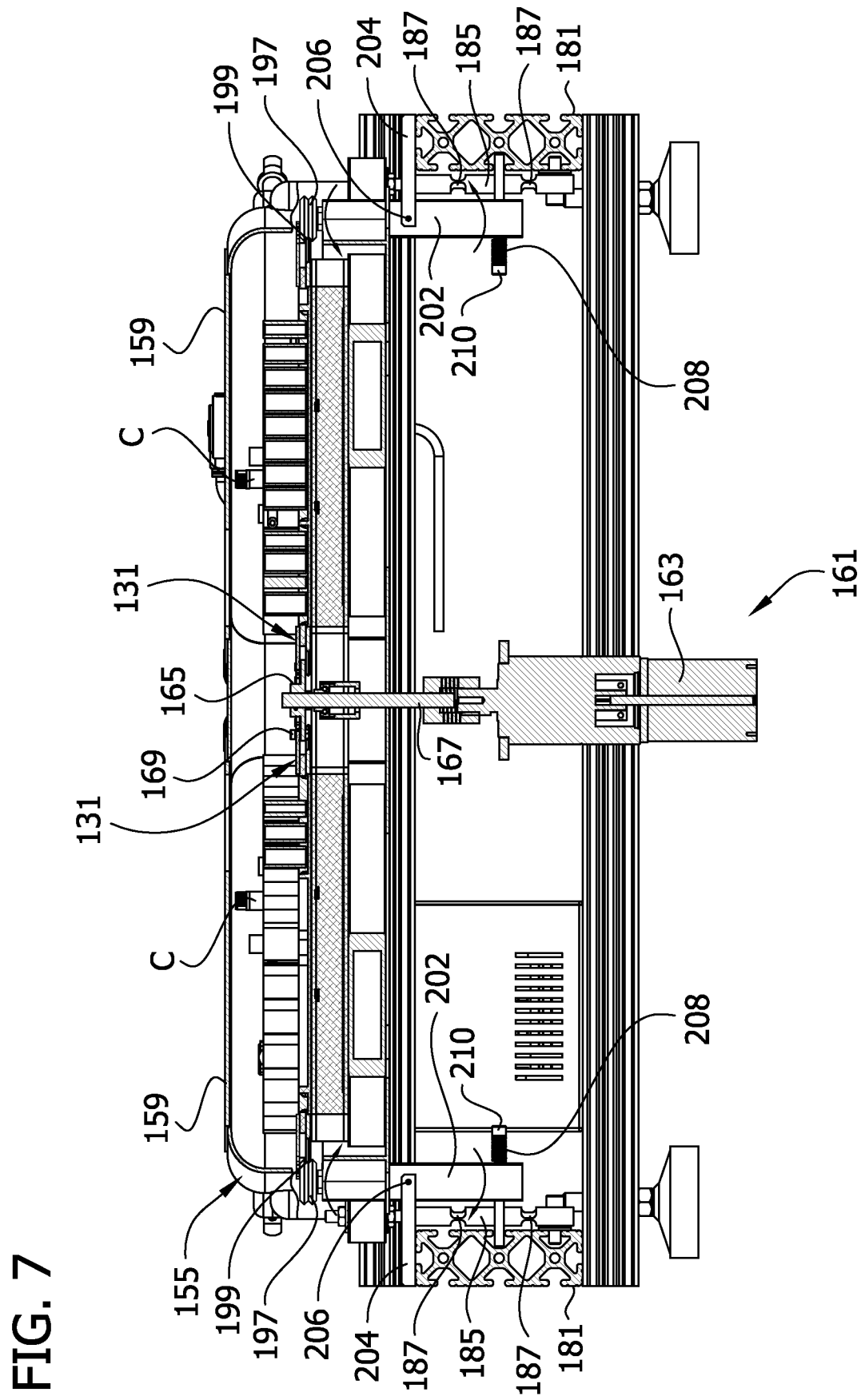


FIG. 8

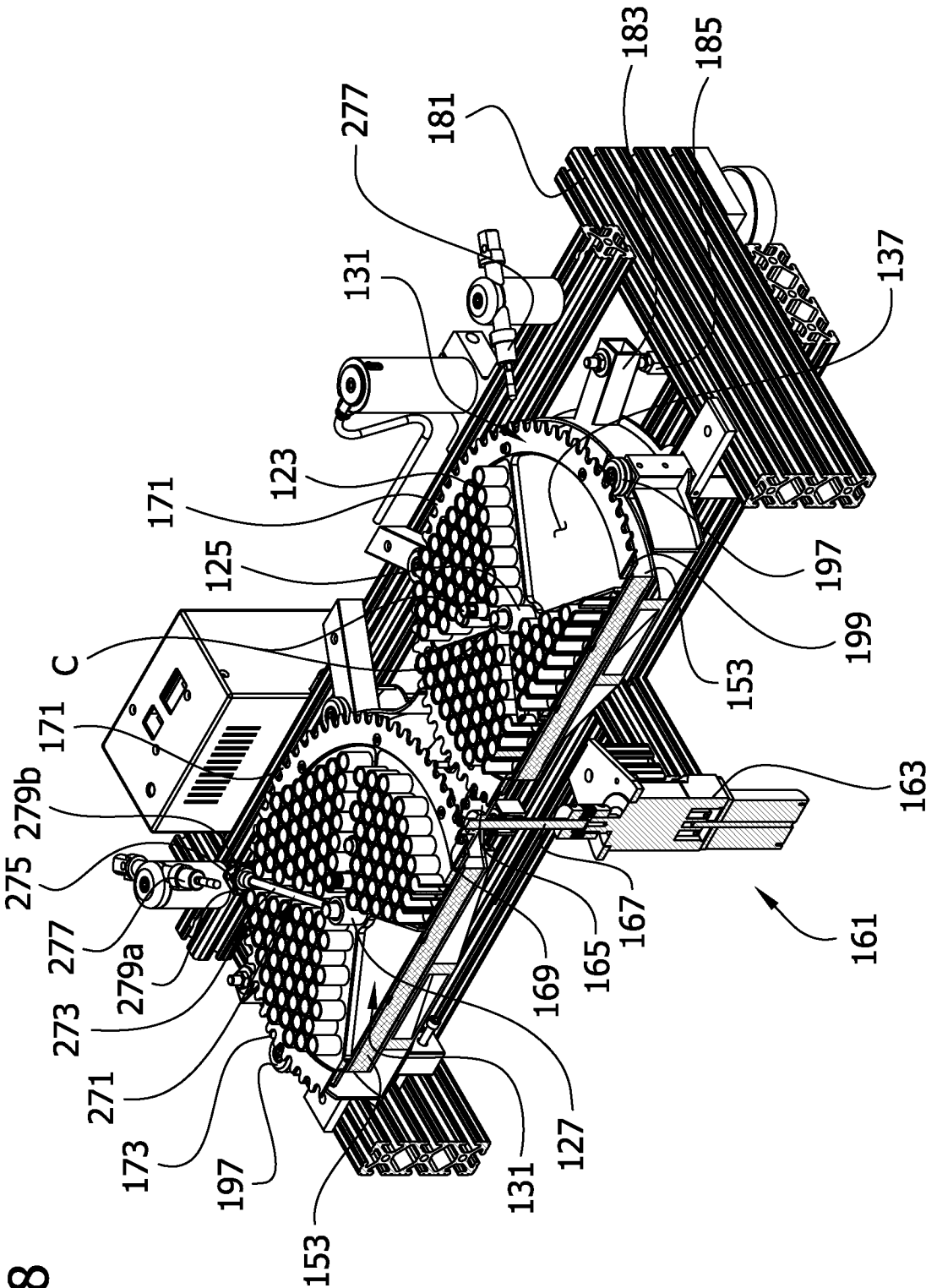


FIG. 9

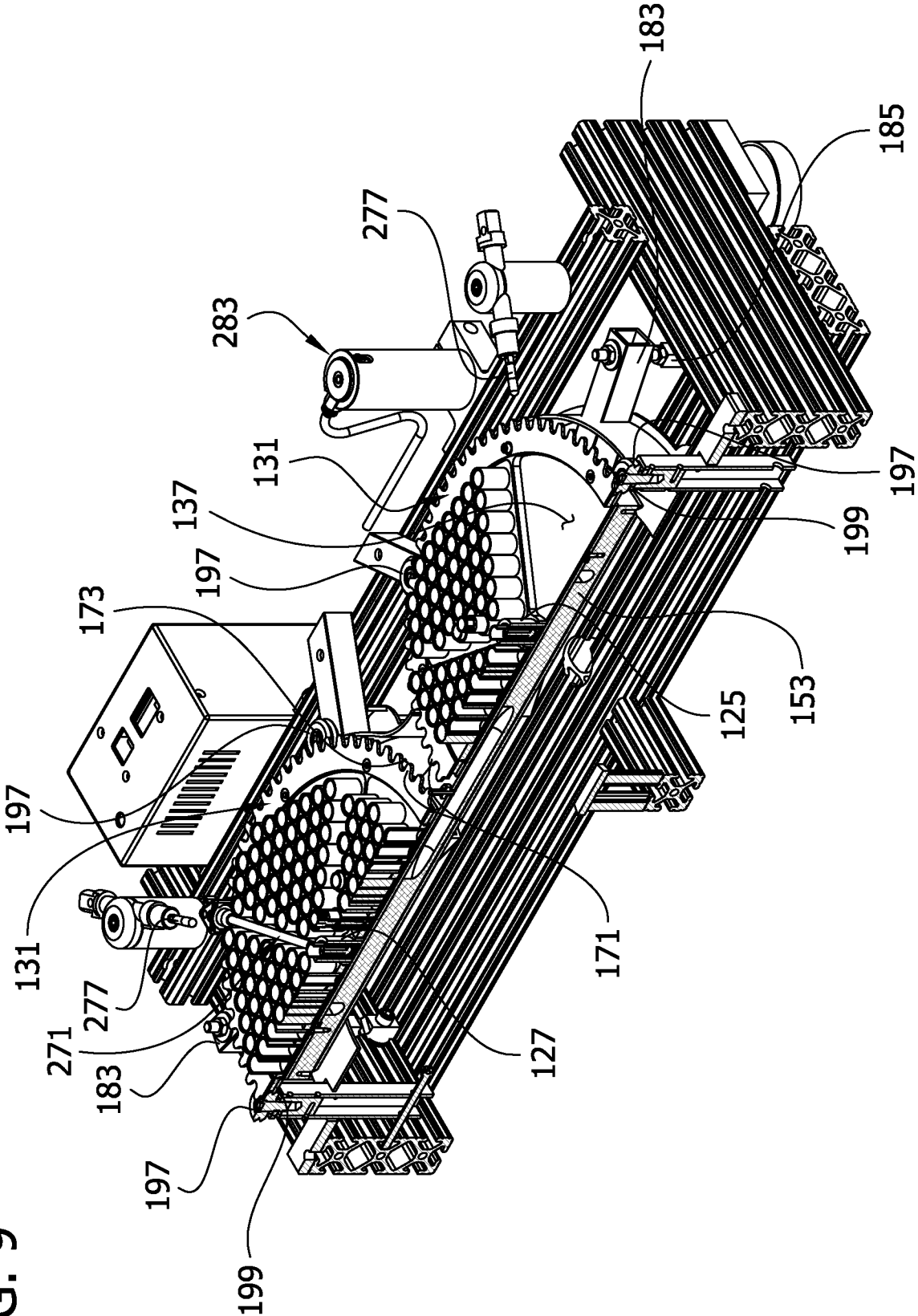


FIG. 10

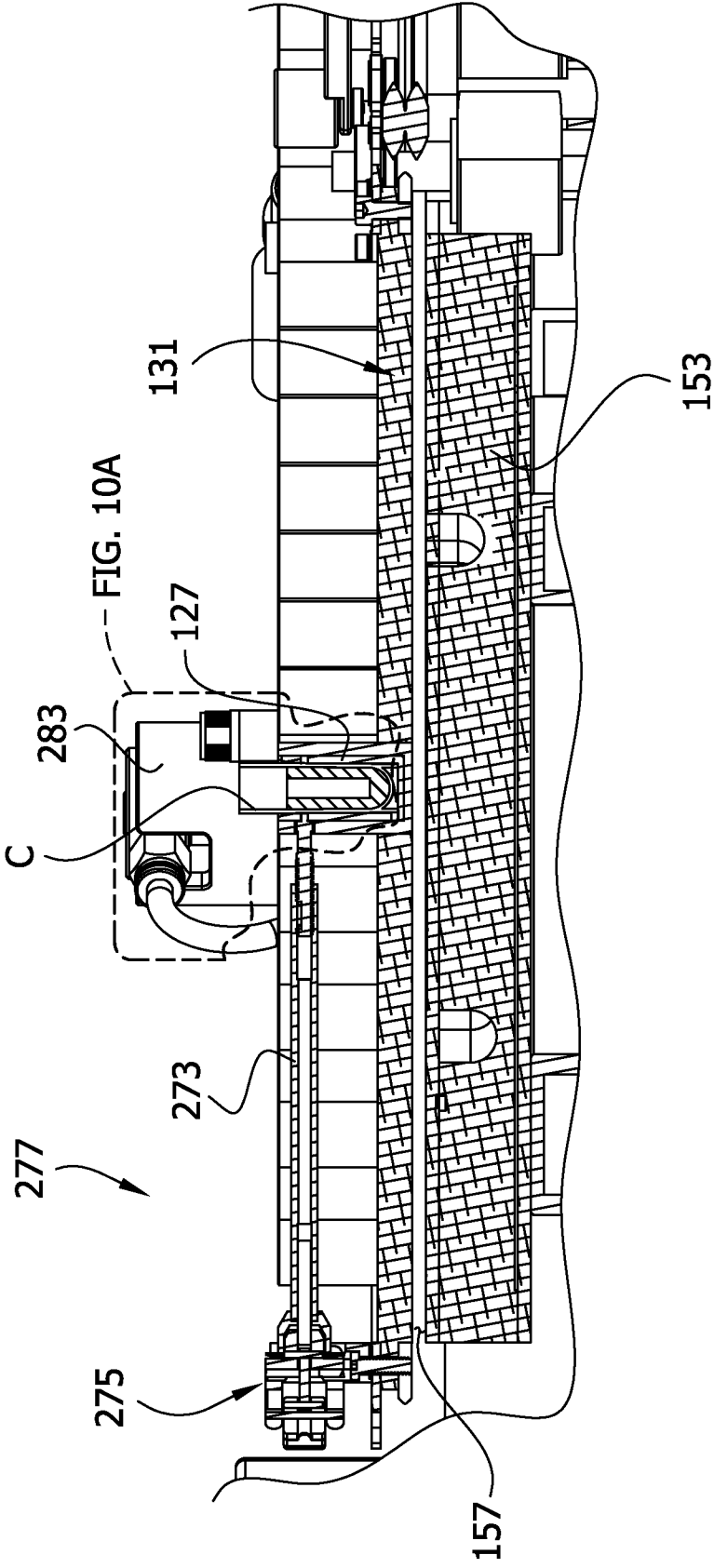


FIG. 10A

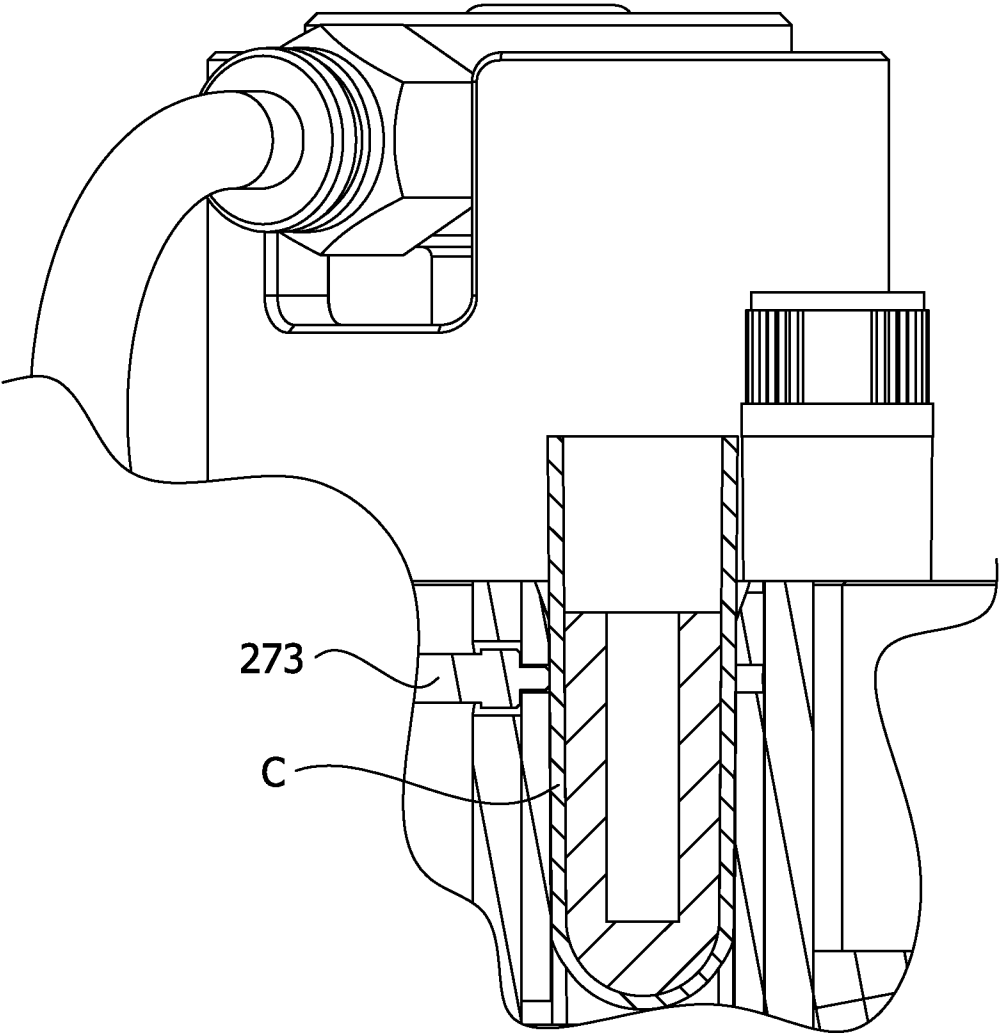


FIG. 11

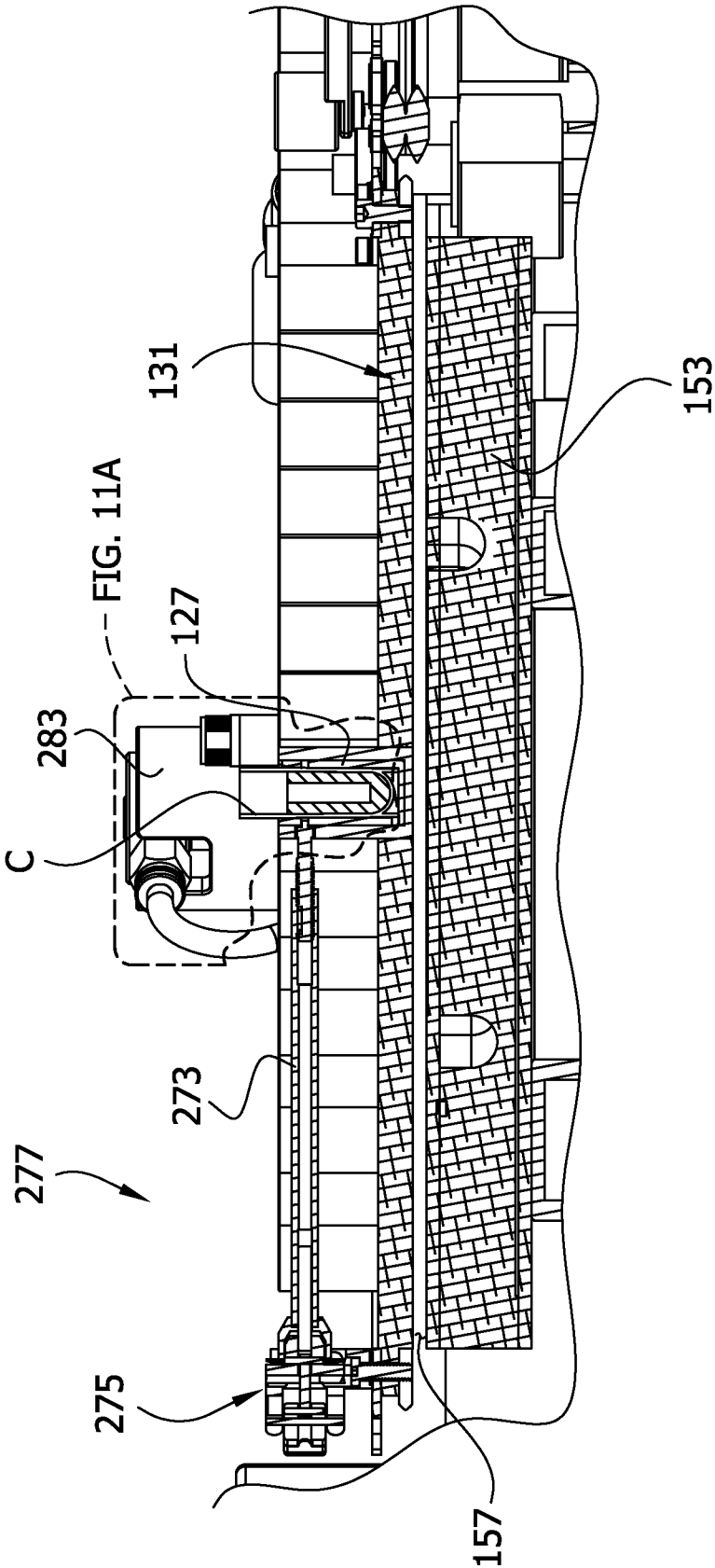


FIG. 11A

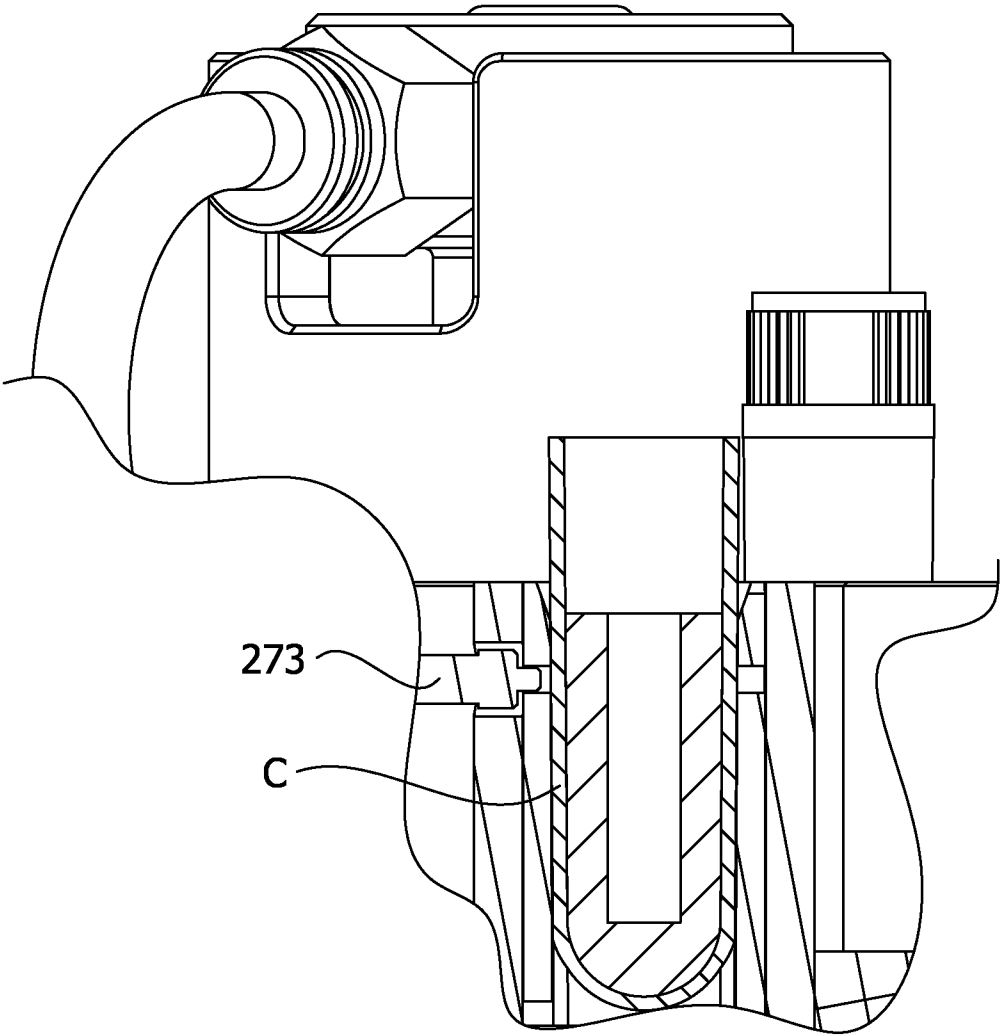
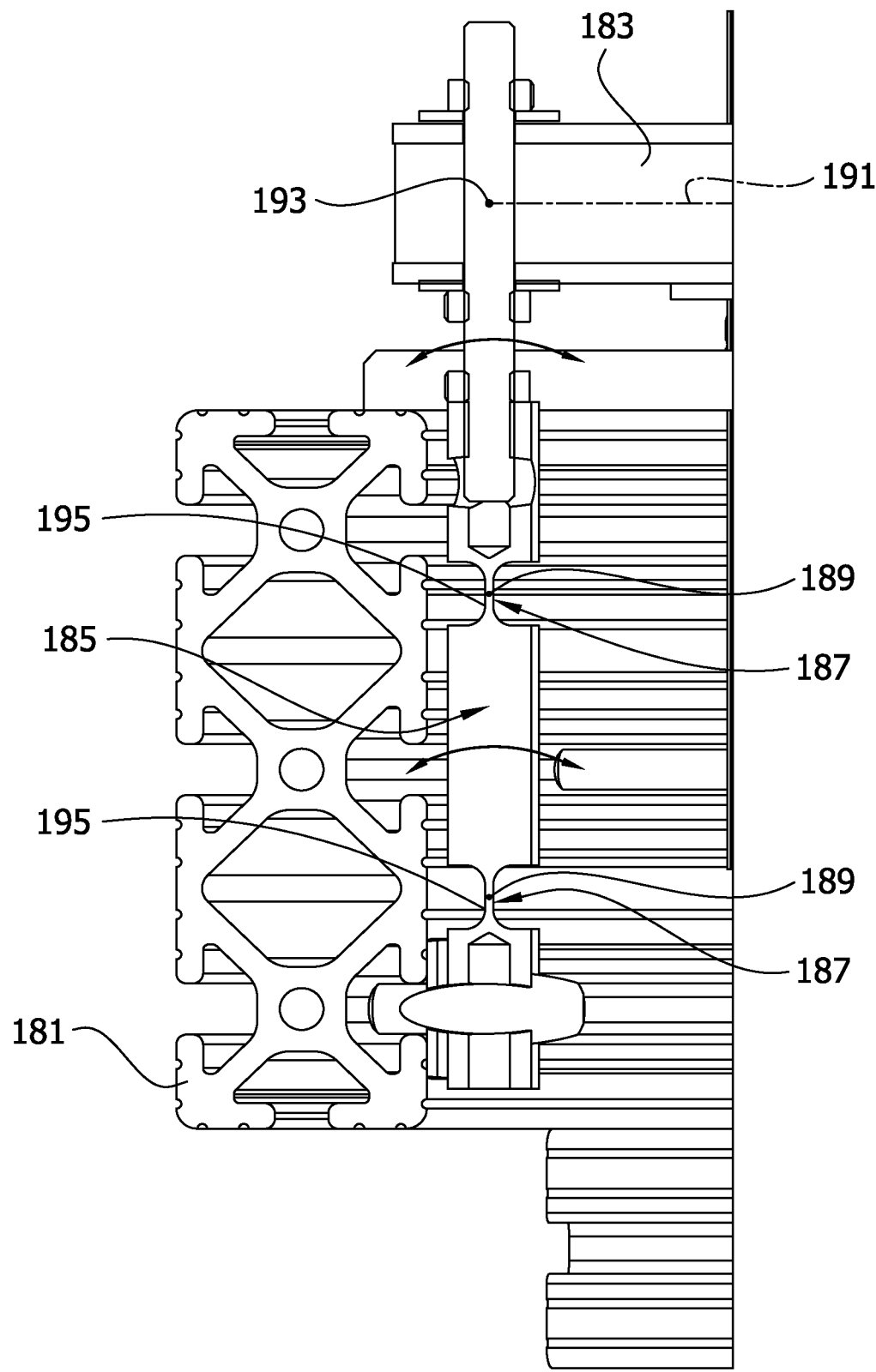
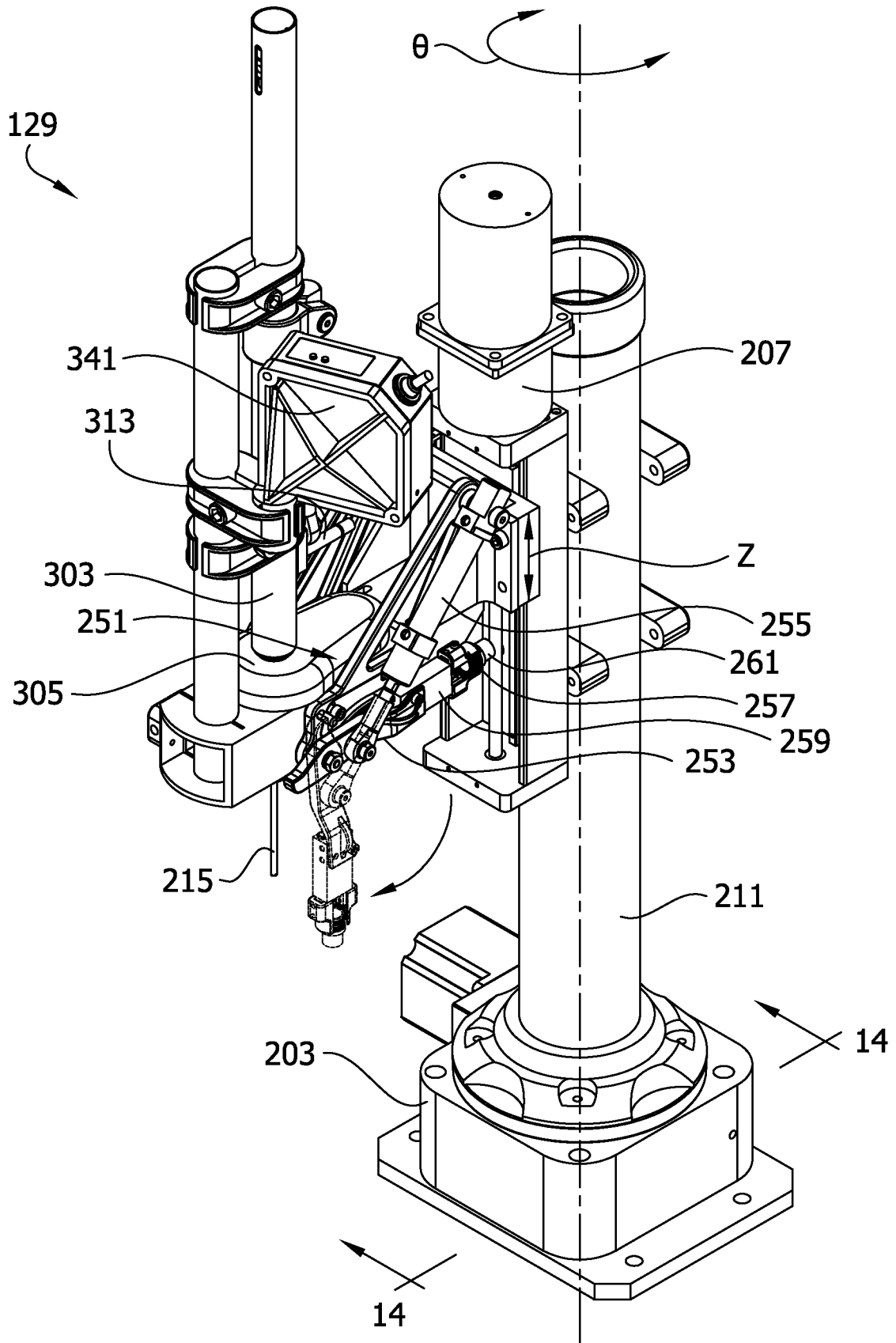


FIG. 12



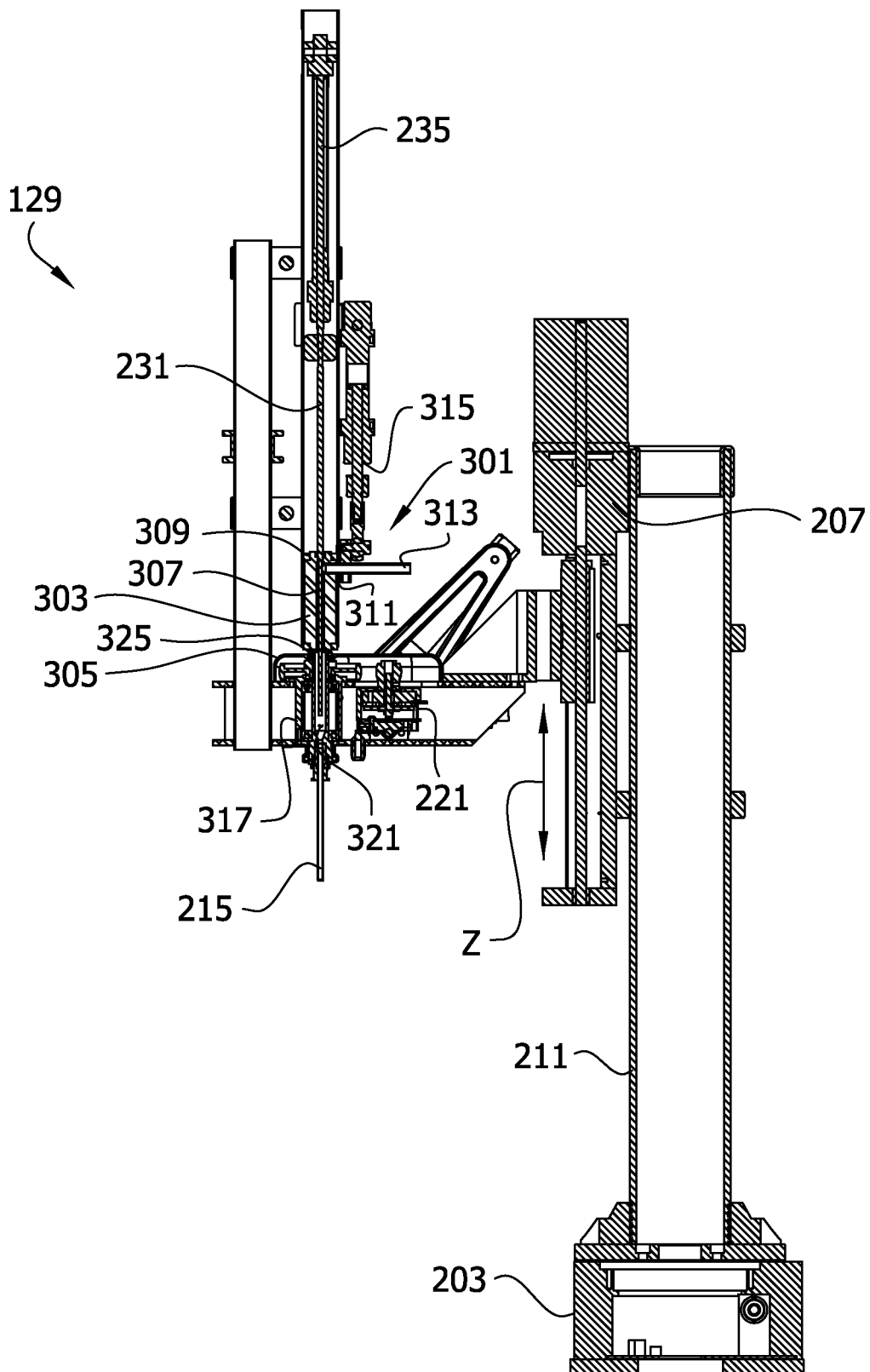
15/33

FIG. 13



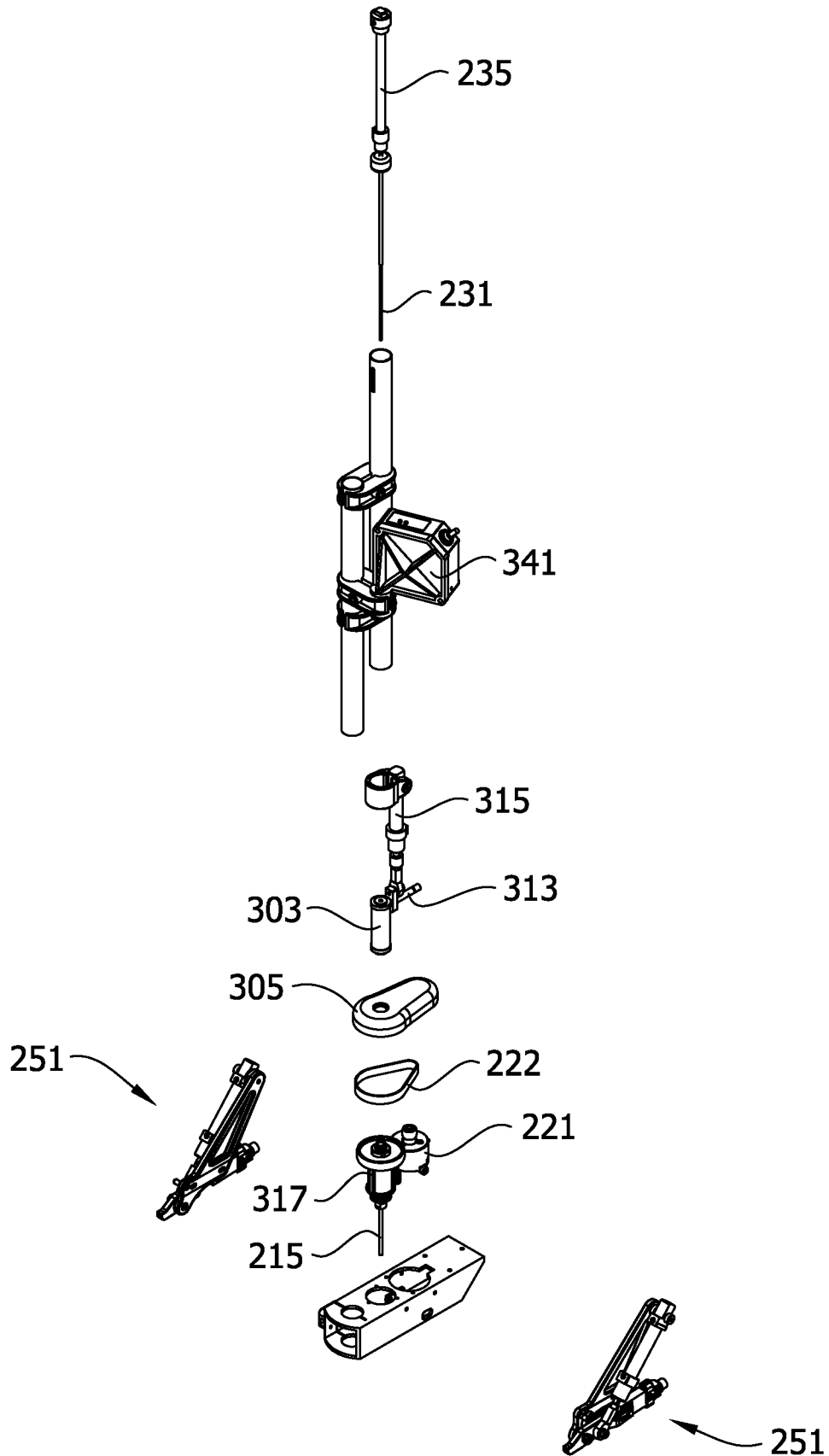
16/33

FIG. 14



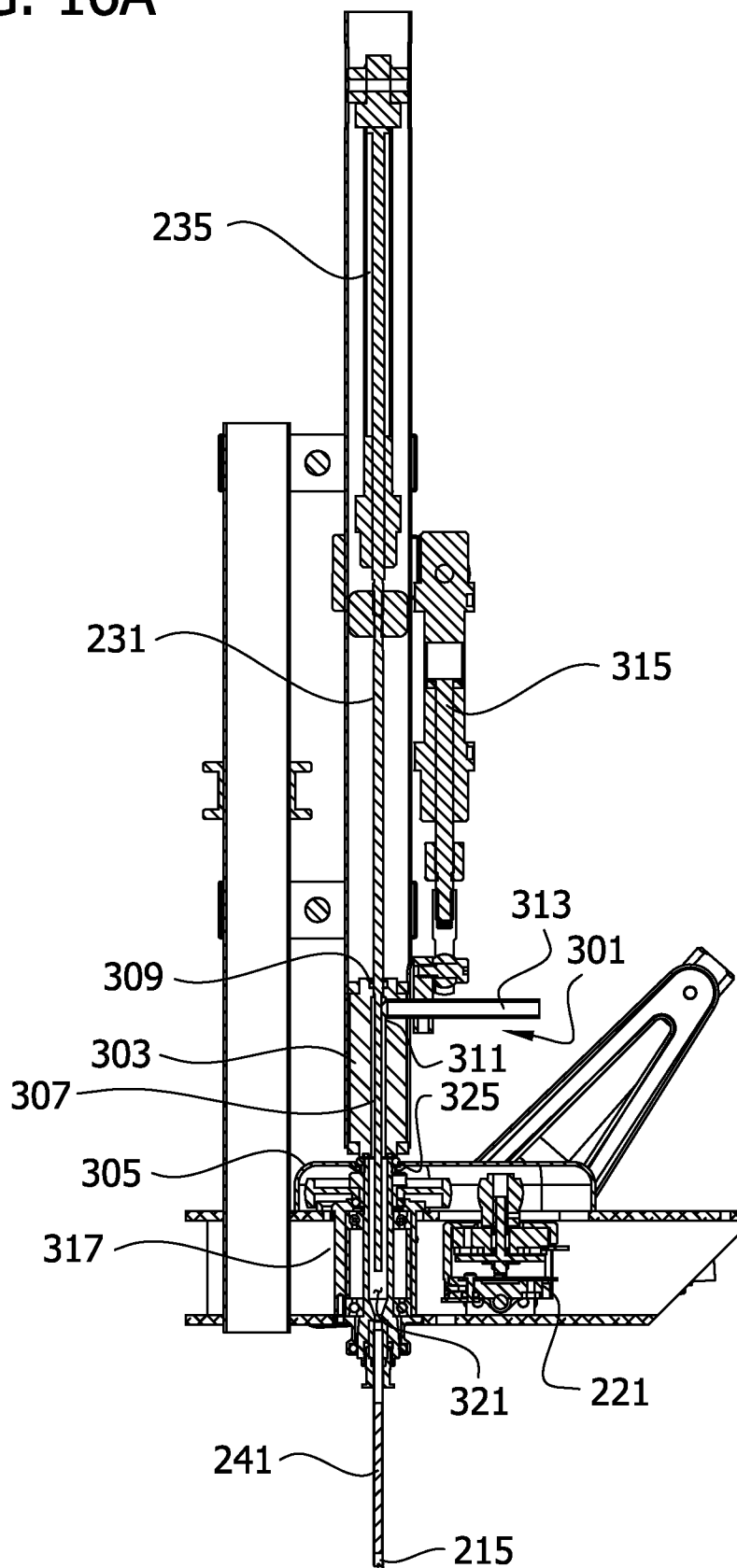
17/33

FIG. 15



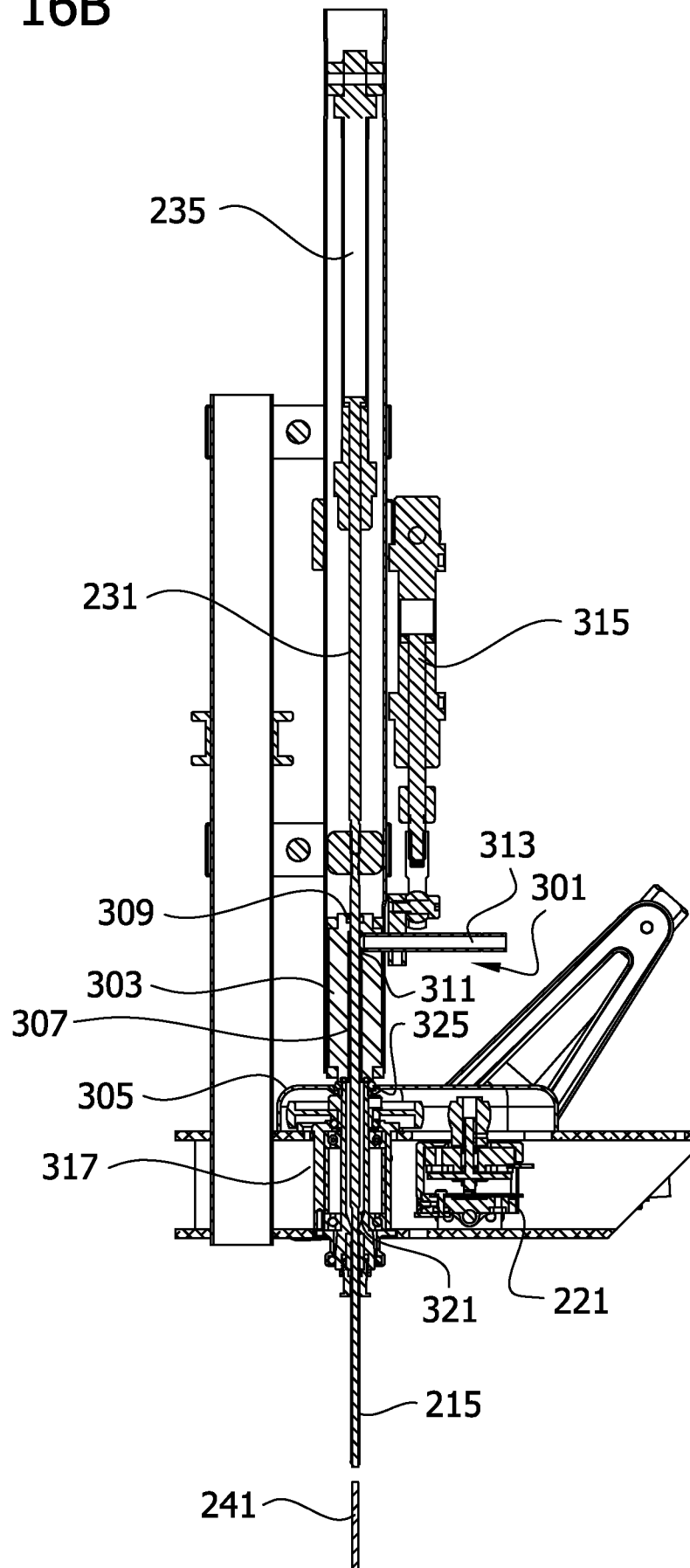
18/33

FIG. 16A



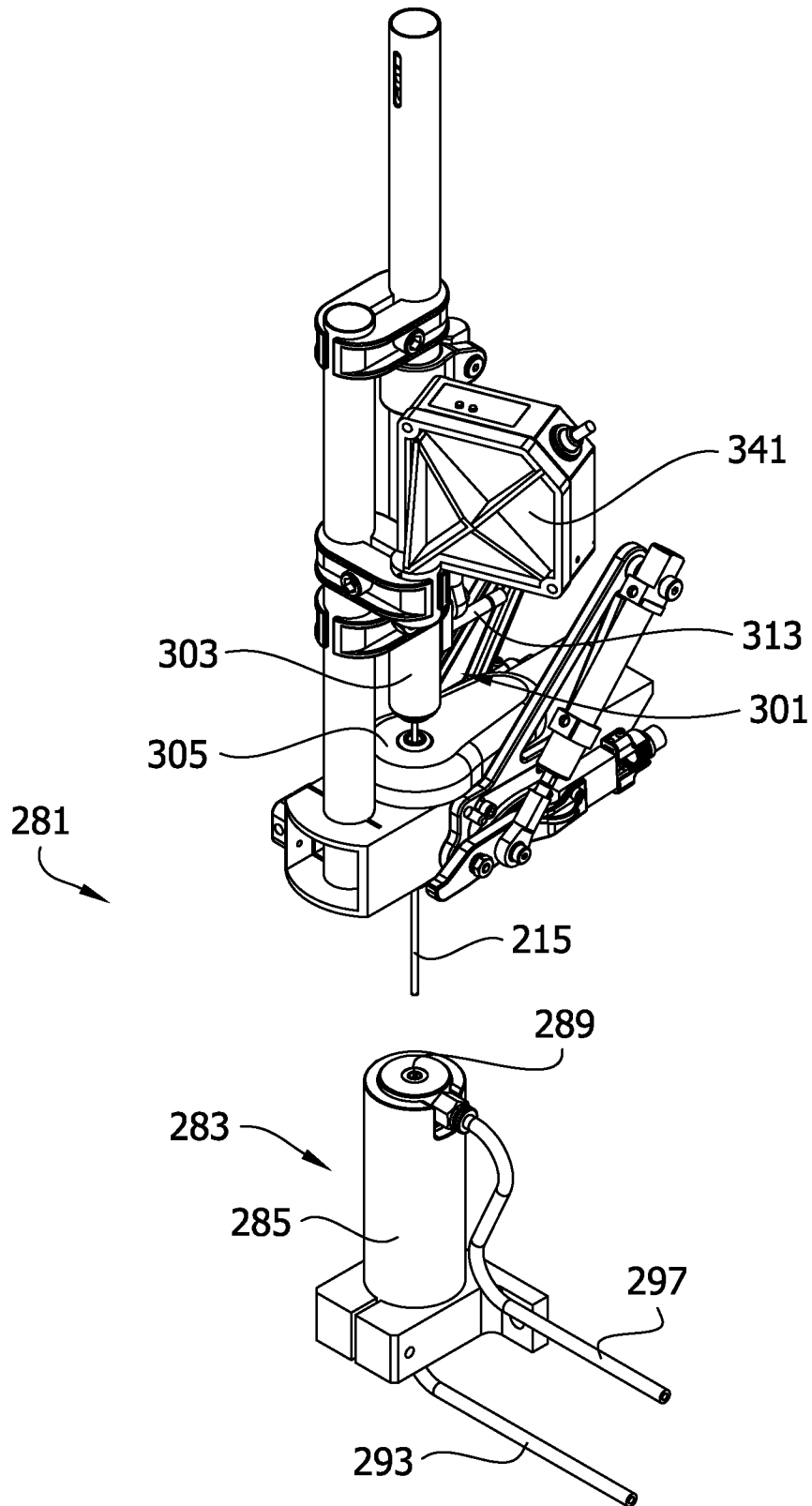
19/33

FIG. 16B



20/33

FIG. 17A



21/33

FIG. 17B

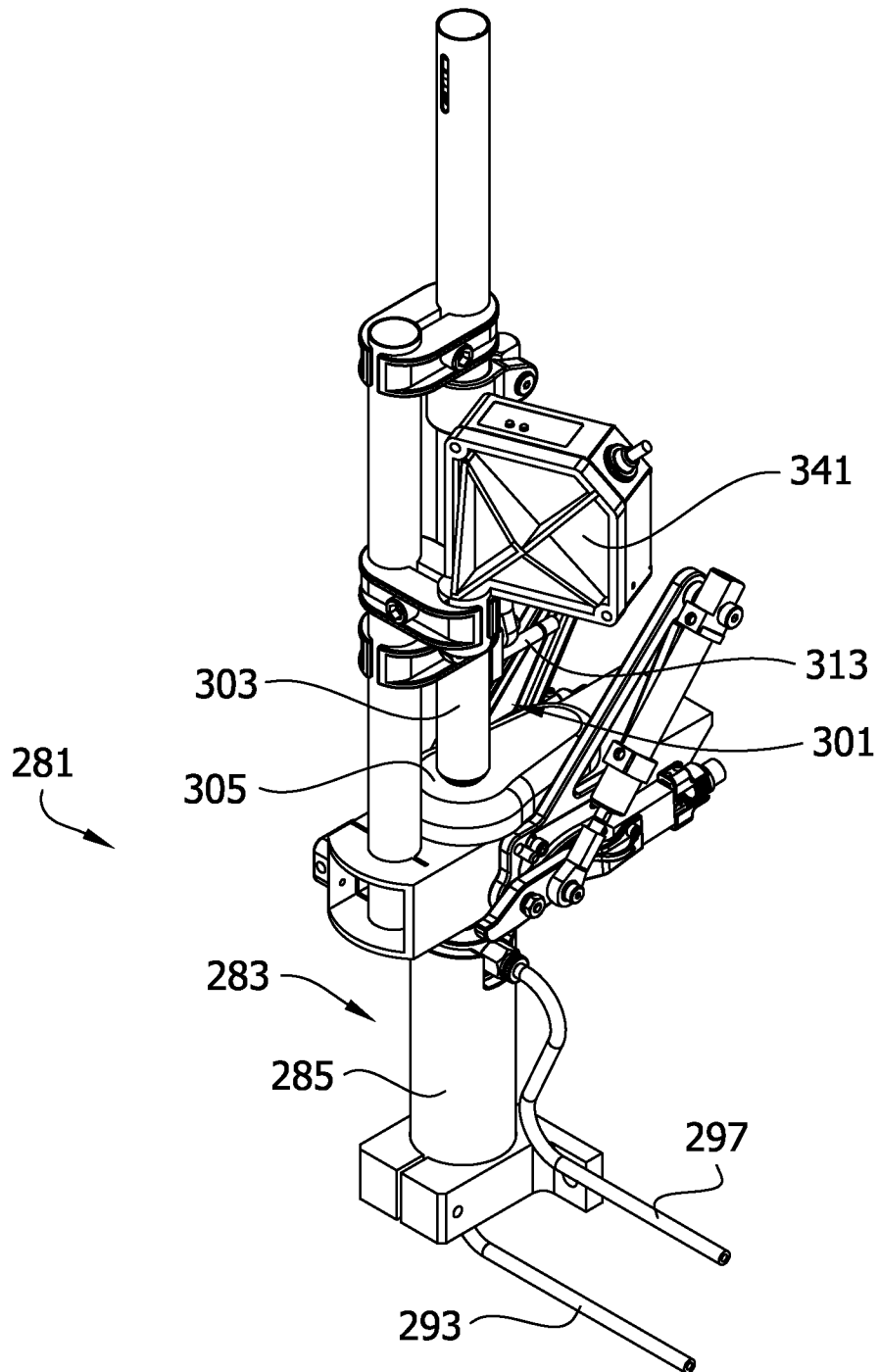
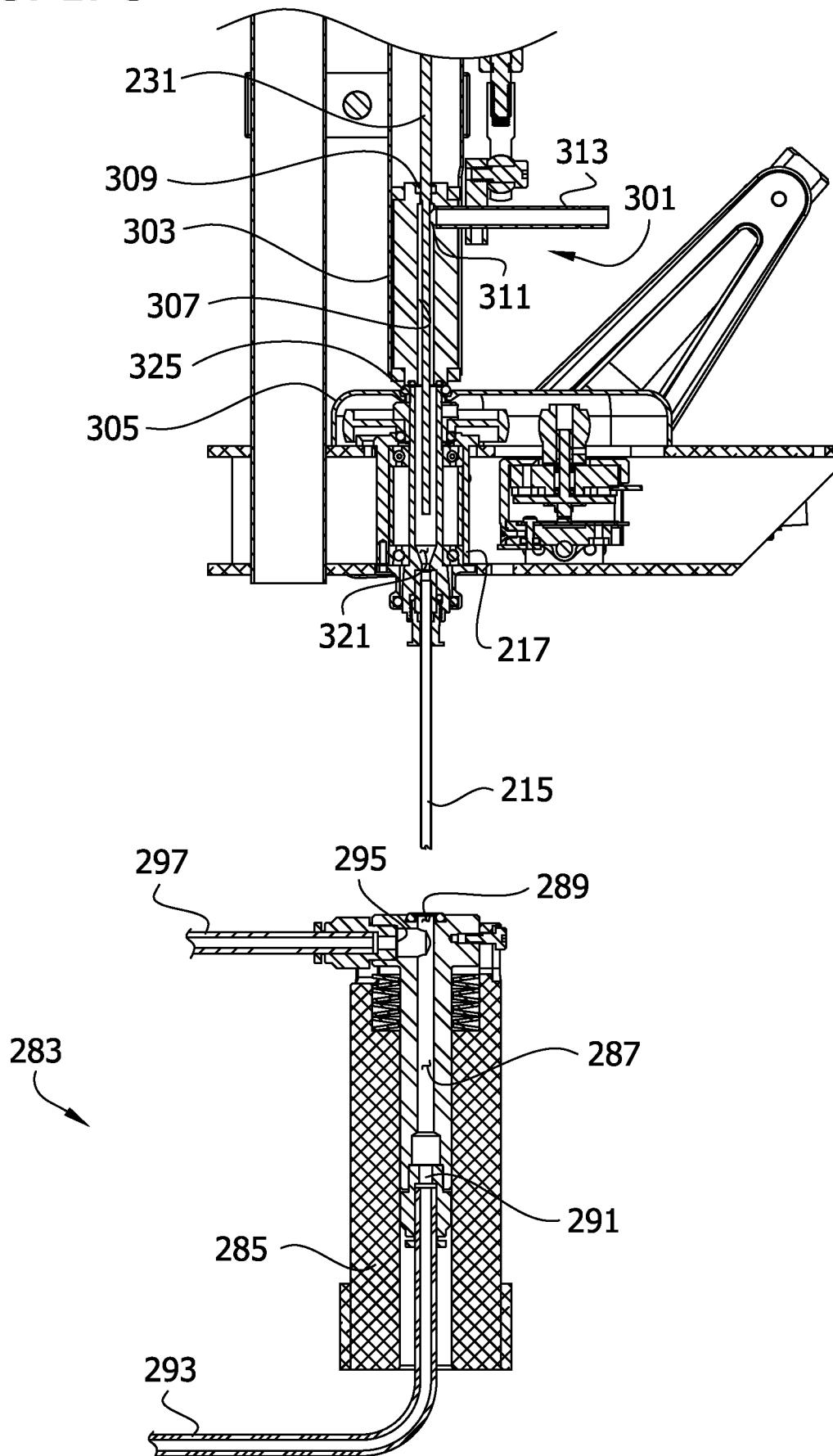


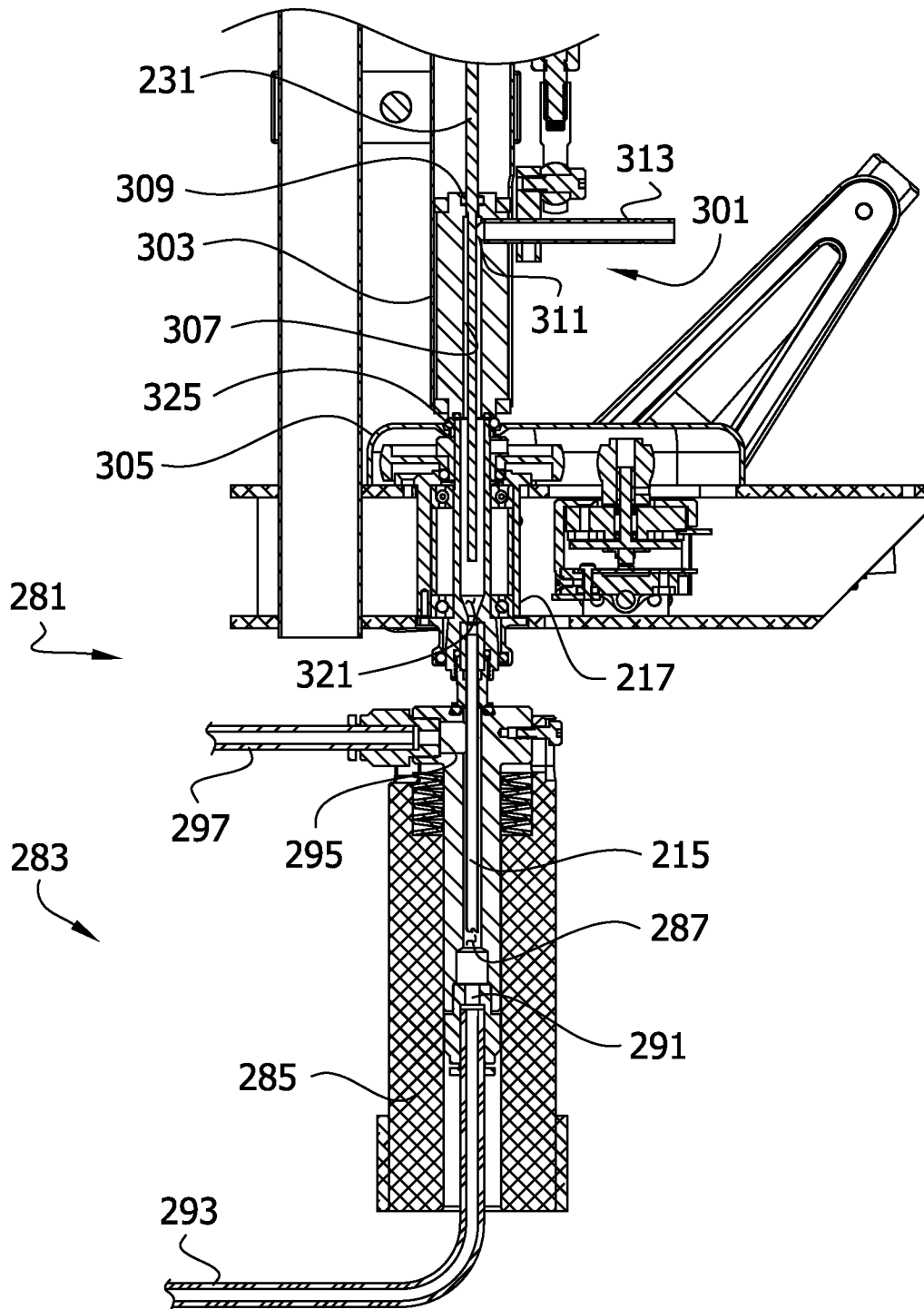
FIG. 17C

22/33



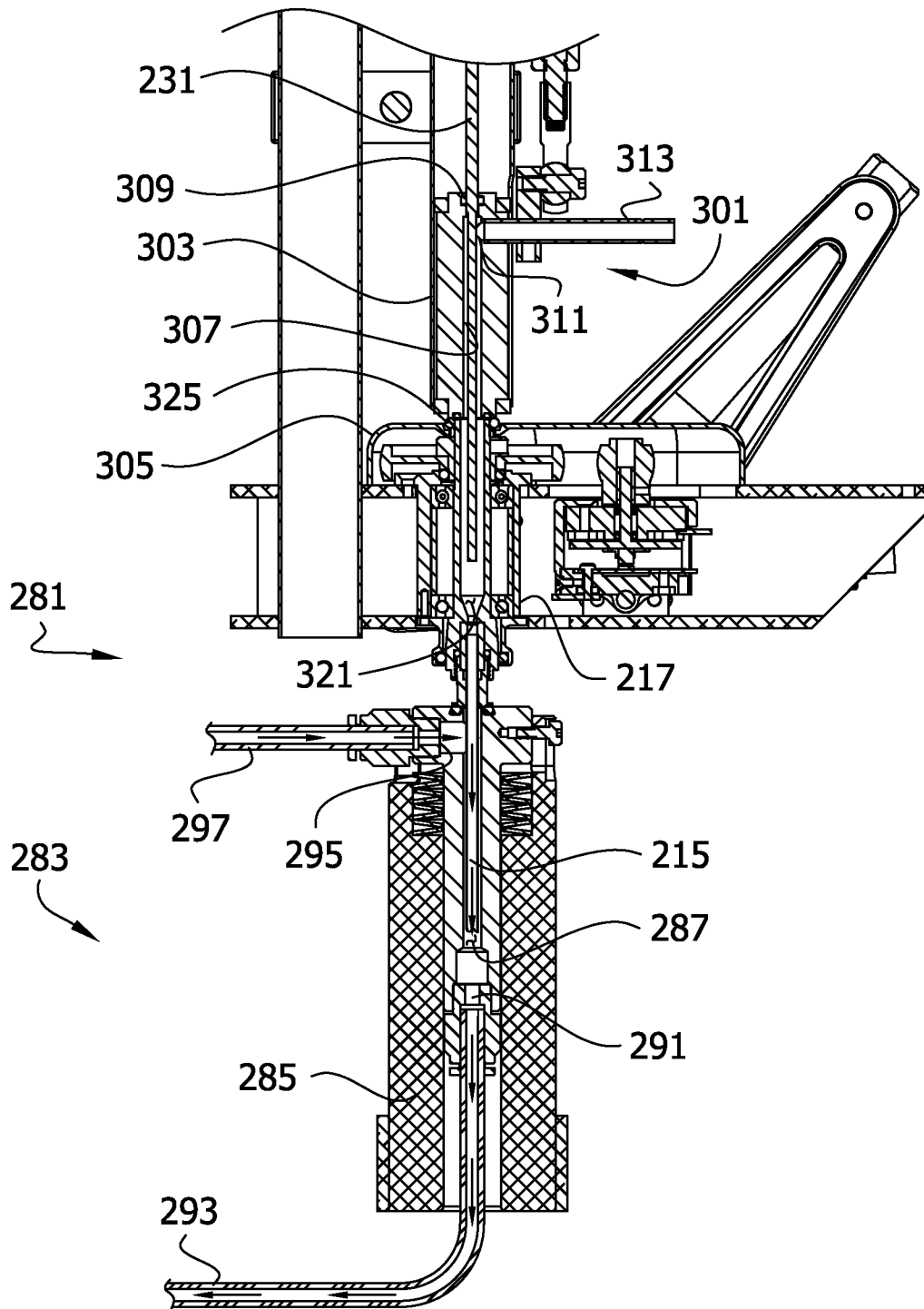
23/33

FIG. 17D



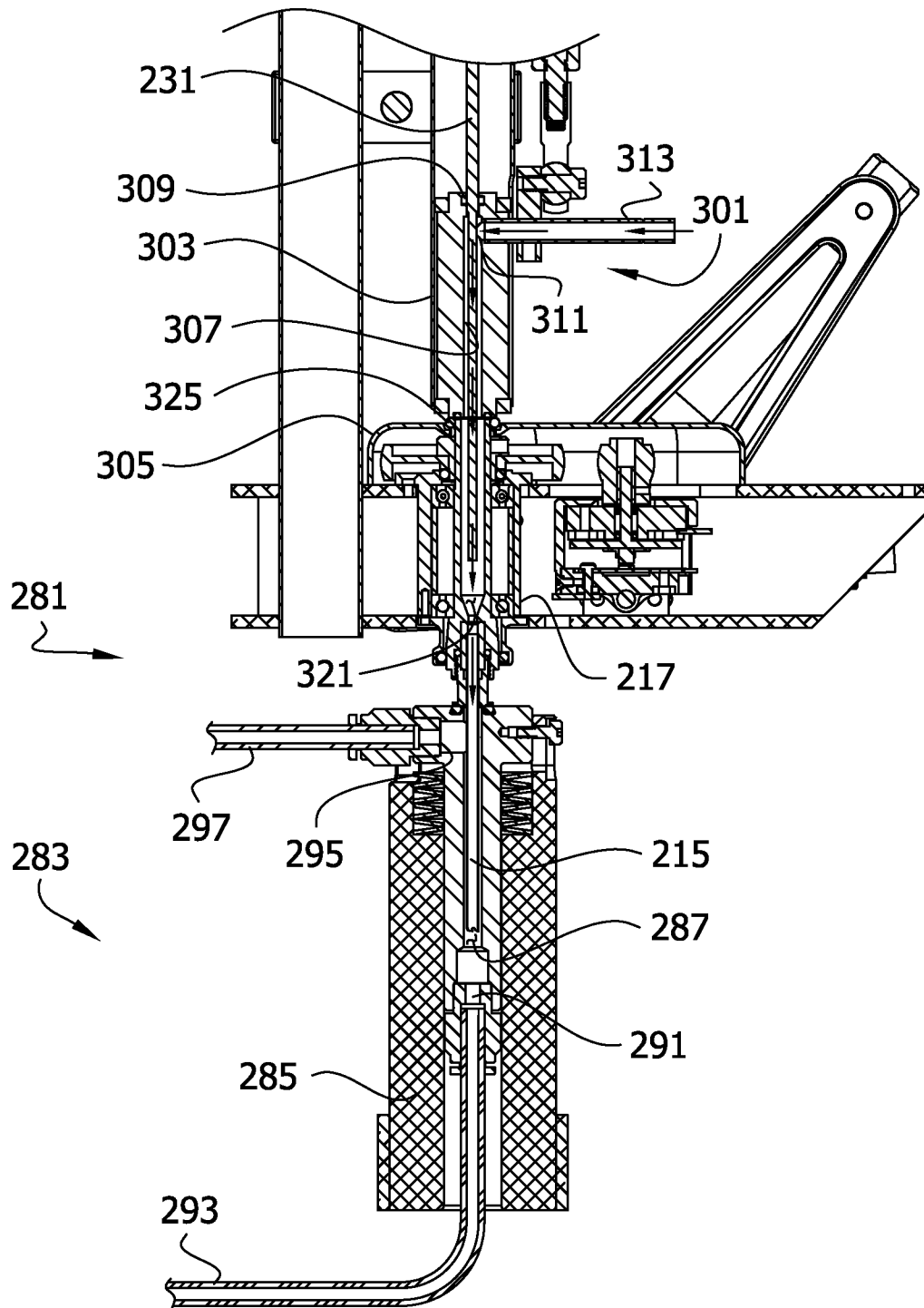
24/33

FIG. 17E



25/33

FIG. 17F



26/33

FIG. 18A

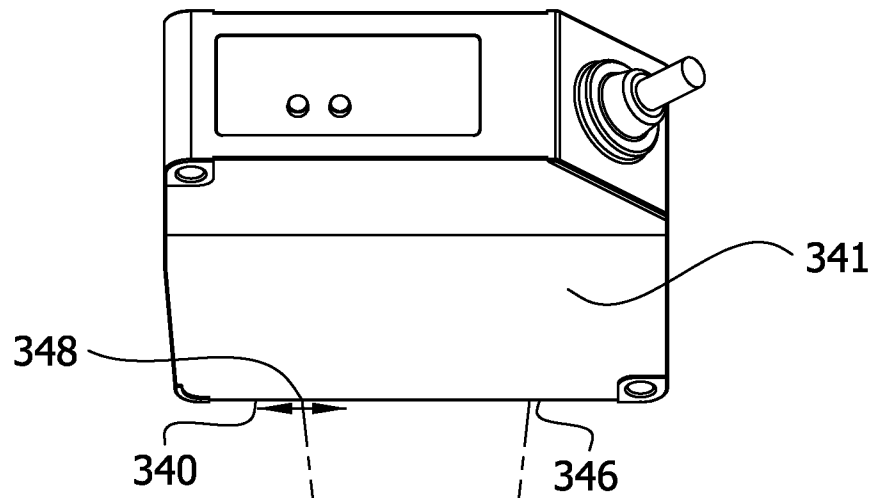
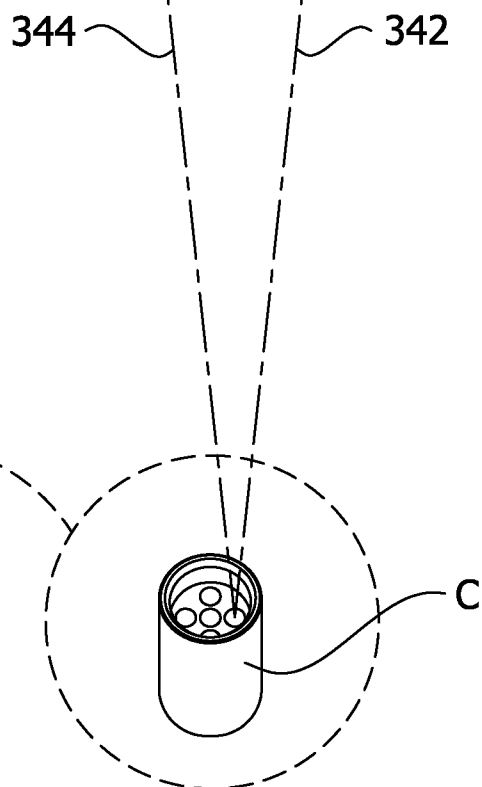


FIG. 18B



27/33

FIG. 18B

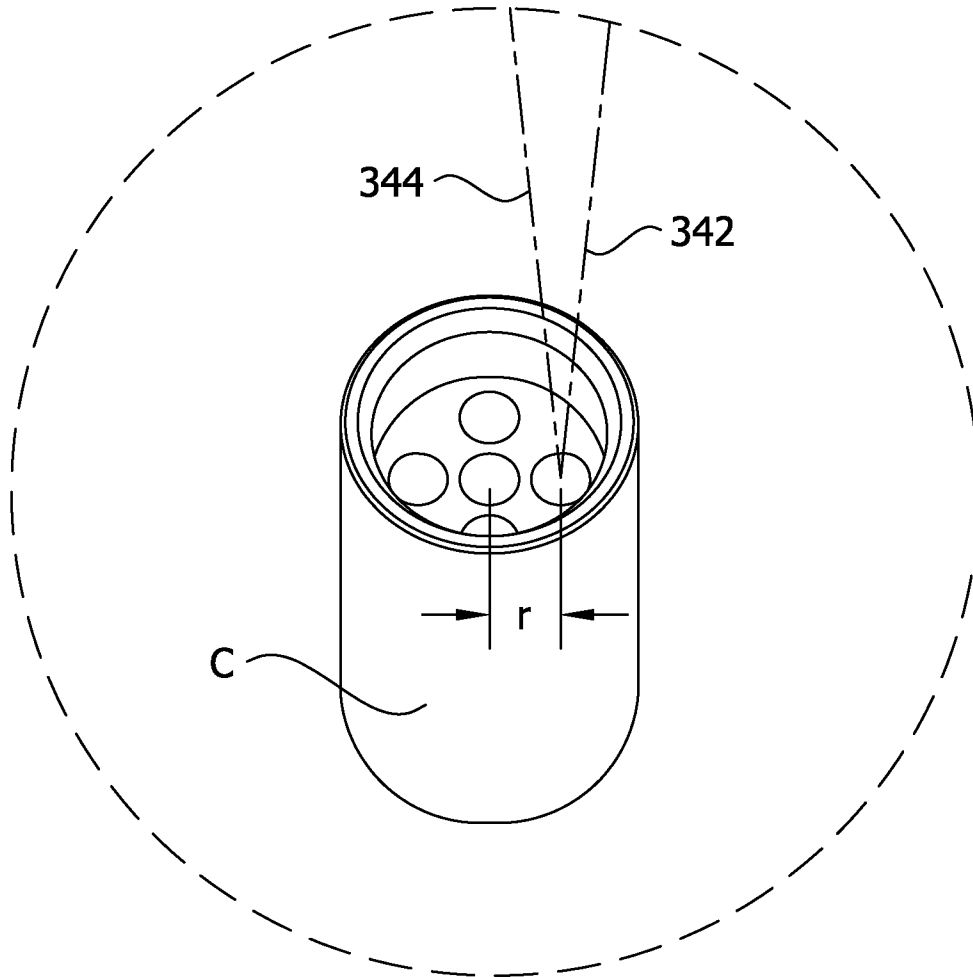


FIG. 18C

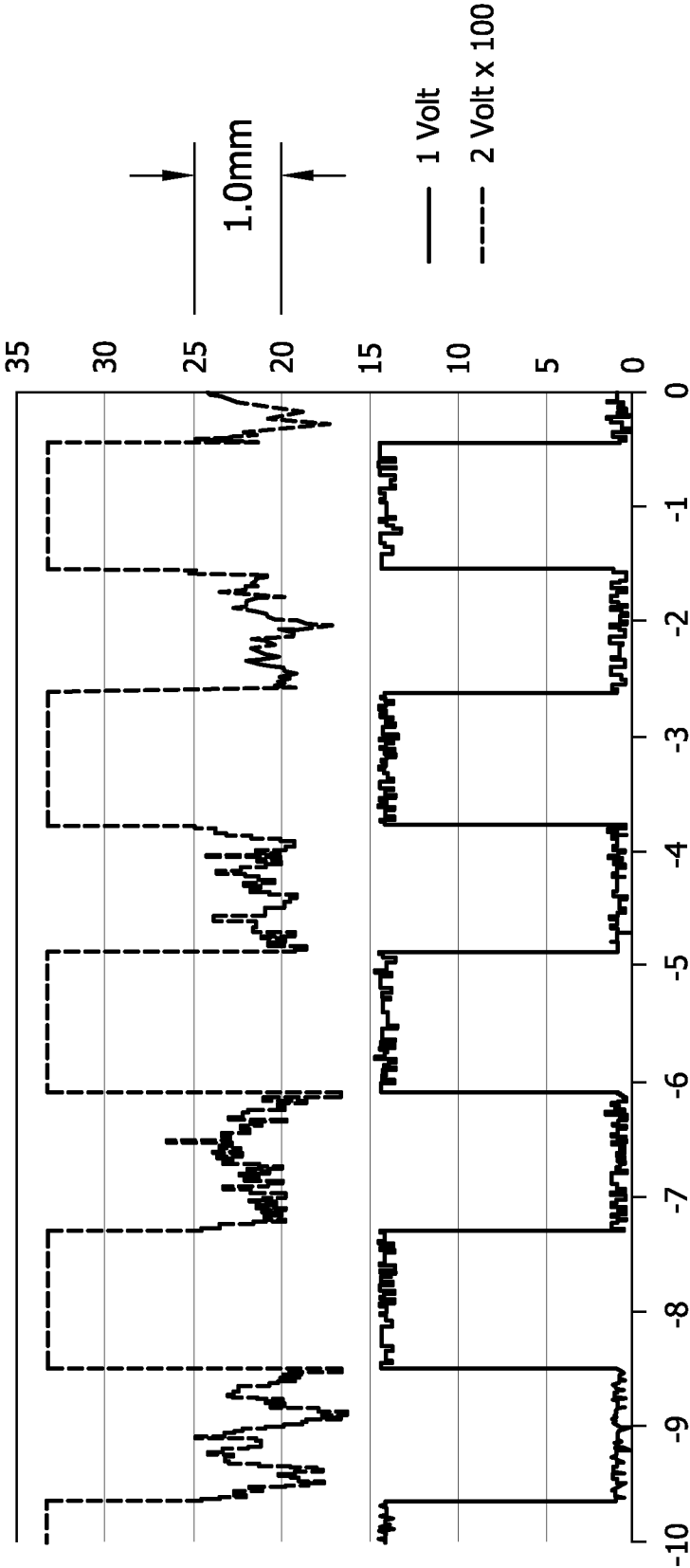


FIG. 18D

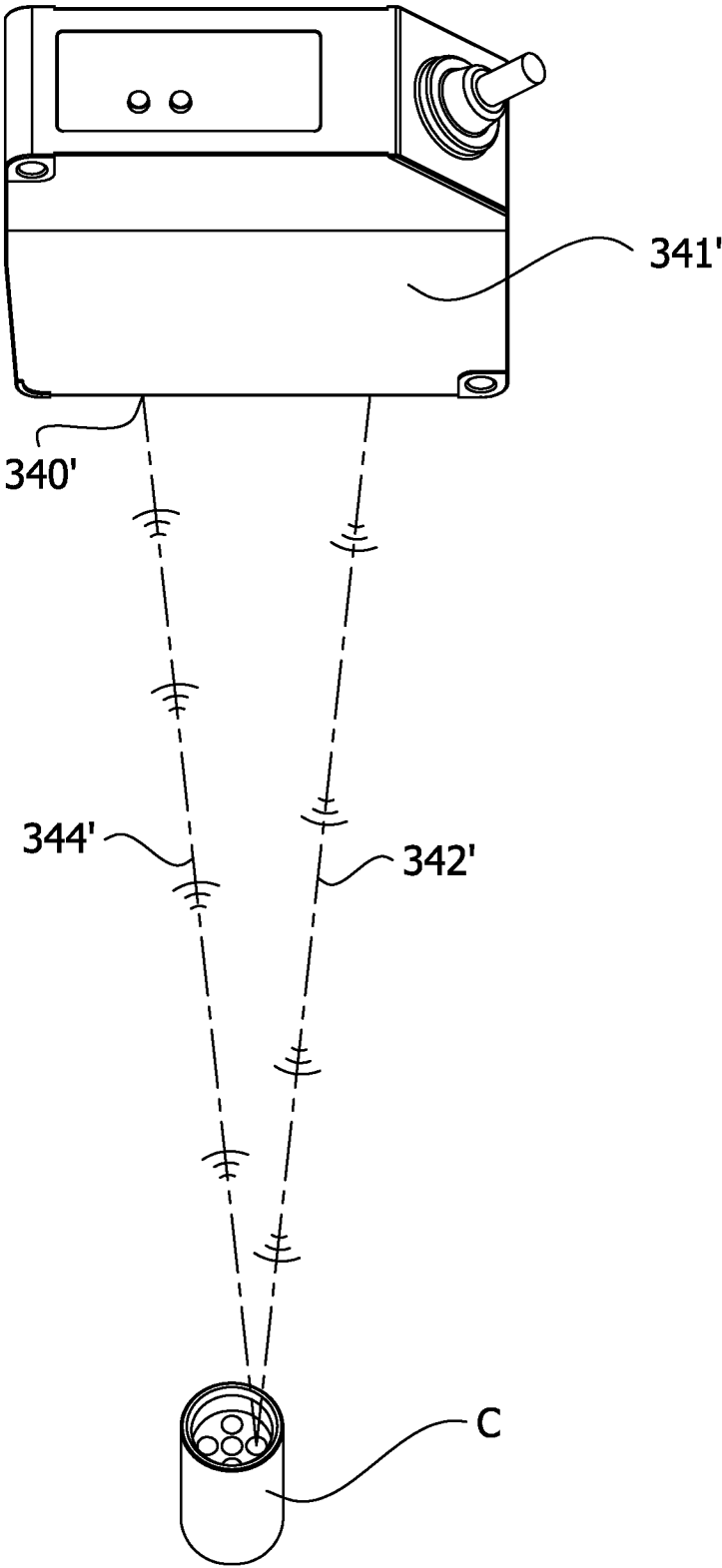
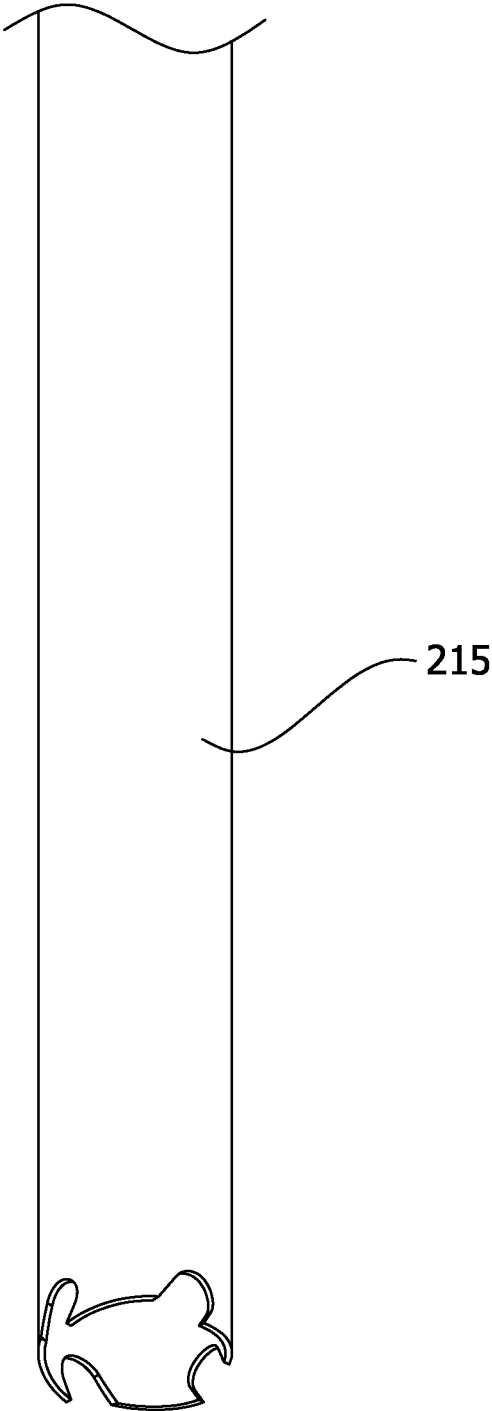
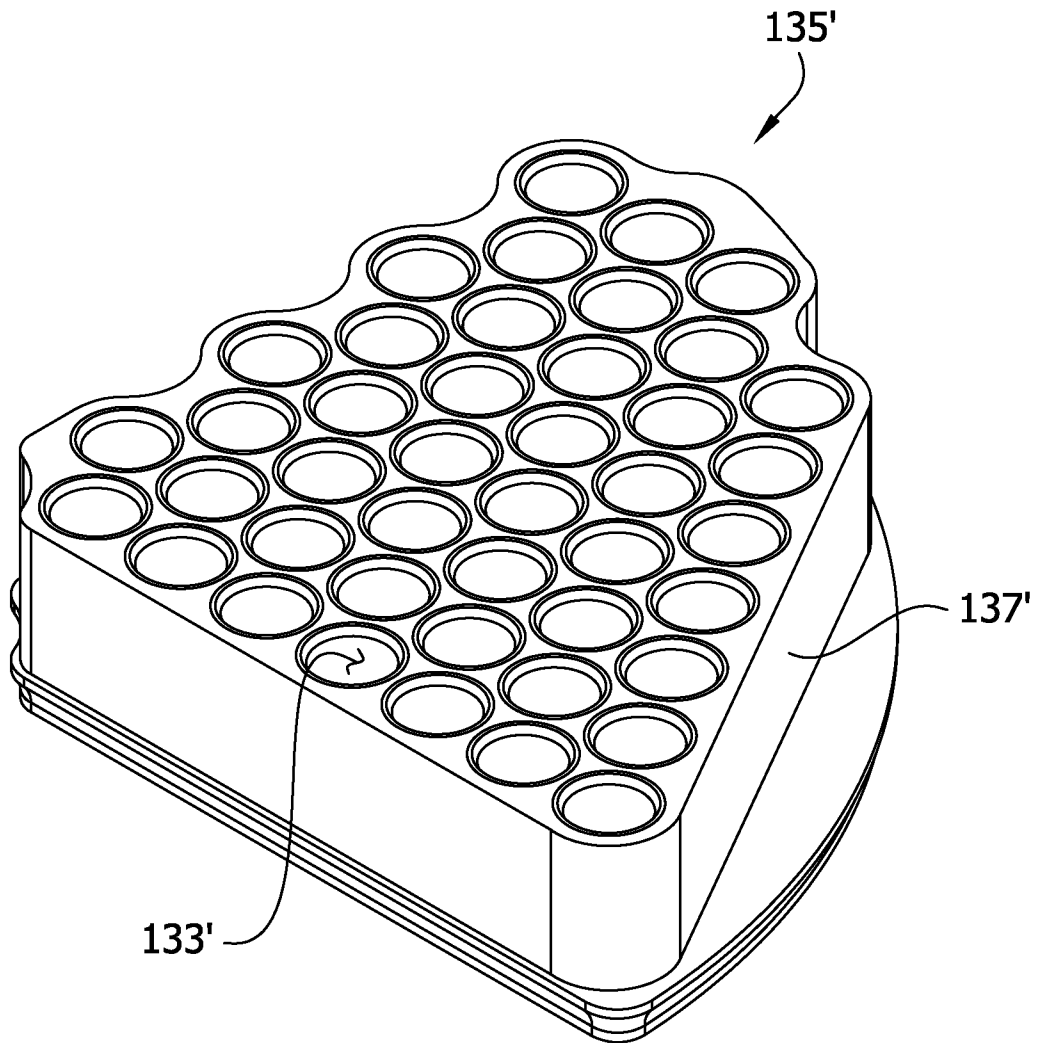


FIG. 19



31/33

FIG. 20



32/33

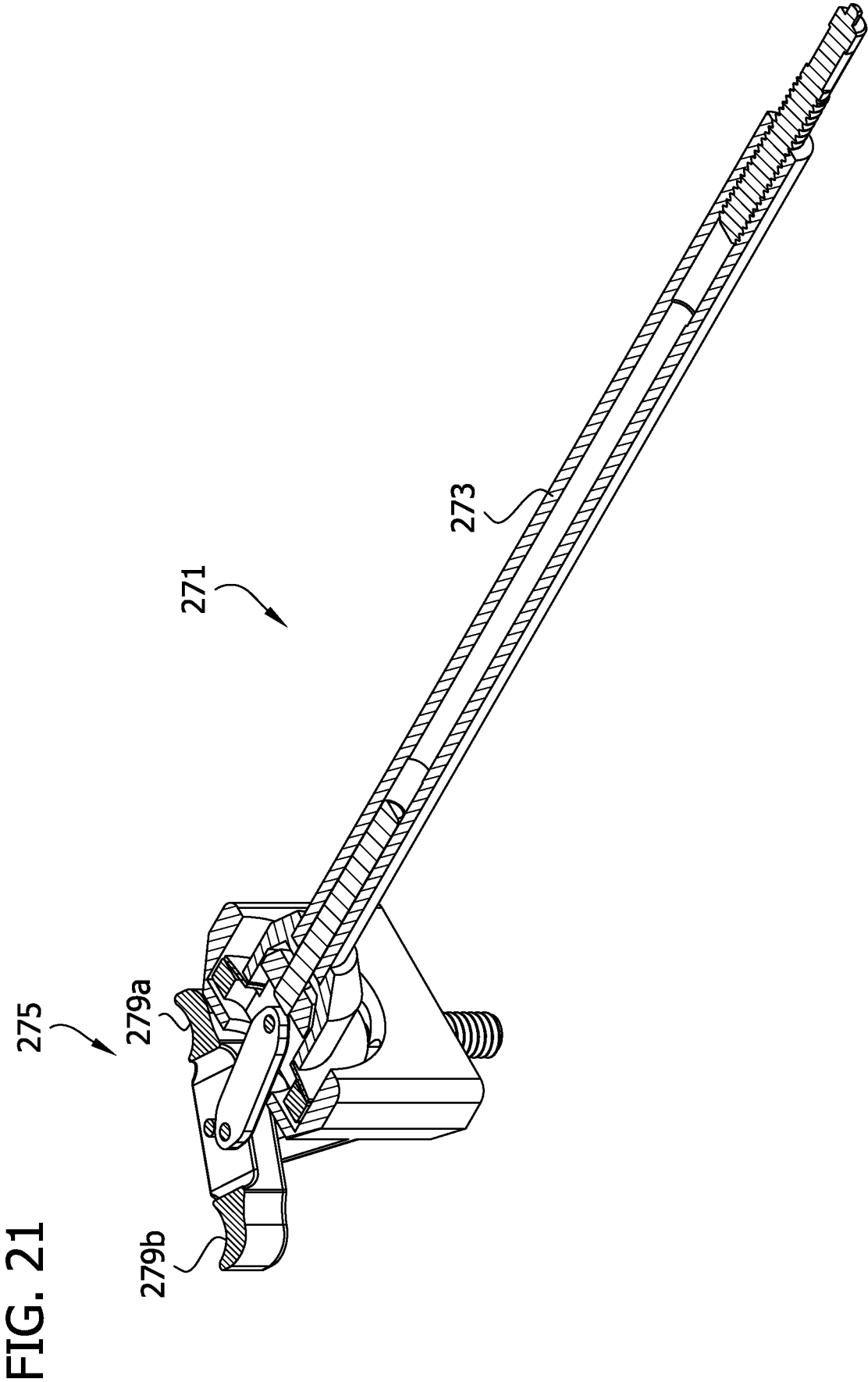


FIG. 22

