VICI Valco Instruments Co. Inc.

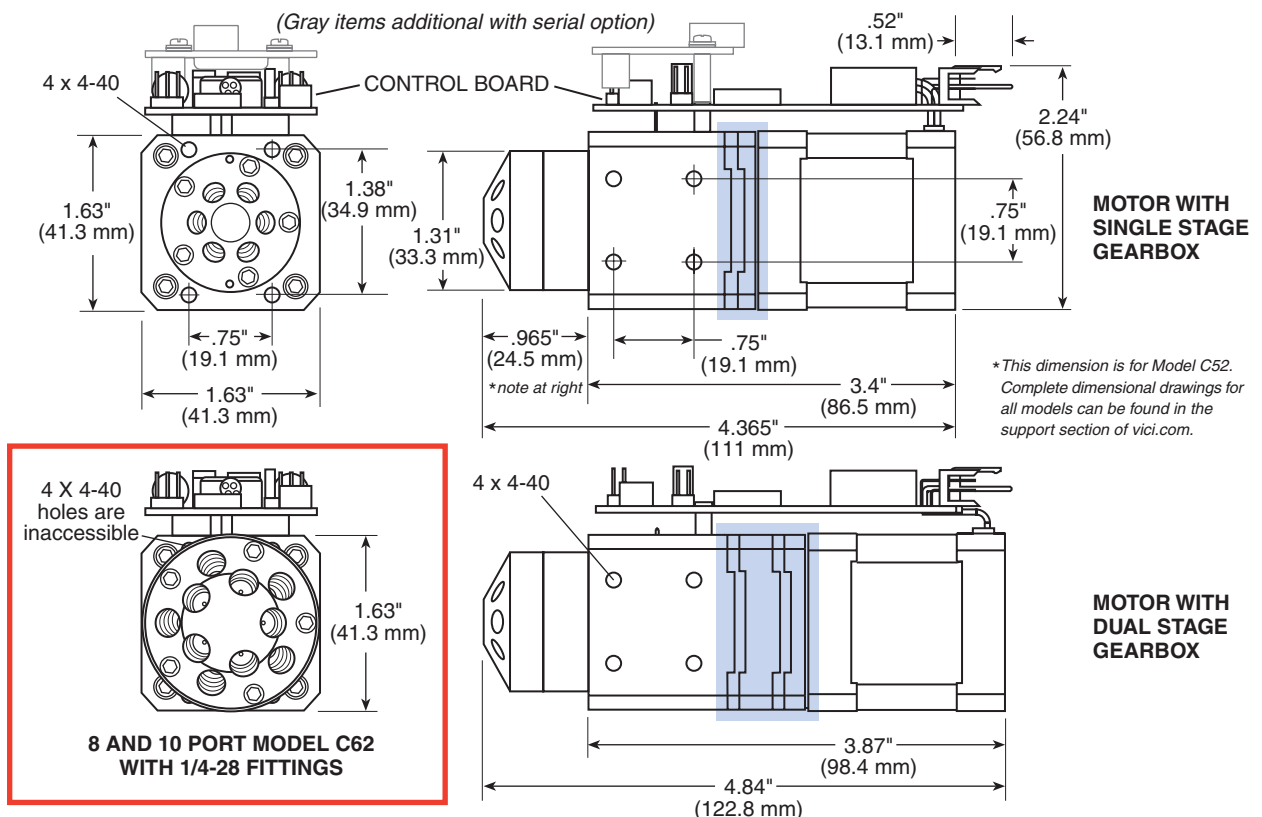# Cheminert® Model C52 and C62(Z) Injectors

Installation and Maintenance

The Cheminert® C52 (HPLC) and C62 (LC) series injectors are integrated motor/valve assemblies designed specifically to be built into OEM systems.

Initial Precautions

After unpacking the injector, leave the protective cap over the valve ports until you are ready to install the unit. As supplied, all surfaces are clean and free of contaminants, and must be kept clean to prevent valve damage. Open ports and fittings cause unnecessary risk of particulate matter entering the valve and scratching the sealing surfaces, which is the most frequent cause of premature valve failure.

WARNING

The most common source of particulate and chemical contamination is tubing which has not been properly cleaned before installation in the valve. Failure to observe proper cleanliness procedures during installation of the valve voids the manufacturer's warranty.

(Gray items additional with serial option)

4 x 4-40 — CONTROL BOARD

.52" (13.1 mm)

2.24" (56.8 mm)

1.63" (41.3 mm)

1.38" (34.9 mm)

1.31" (33.3 mm)

.75" (19.1 mm)

MOTOR WITH SINGLE STAGE GEARBOX

.75" (19.1 mm)

1.63" (41.3 mm)

.965" (24.5 mm) *note at right

.75" (19.1 mm)

3.4" (86.5 mm)

4.365" (111 mm)

*This dimension is for Model C52. Complete dimensional drawings for all models can be found in the support section of vici.com.

4 X 4-40 holes are inaccessible

1.63" (41.3 mm)

8 AND 10 PORT MODEL C62 WITH 1/4-28 FITTINGS

4 x 4-40

MOTOR WITH DUAL STAGE GEARBOX

3.87" (98.4 mm)

4.84" (122.8 mm)

Figure 1: Dimensions for models with single stage gearbox (top) and dual stage gearbox (bottom). The shading indicates the area to check for a quick model identification.

Valve Schematics and Switching Times

Figure 2:
Valve schematics

	4 port	6 port	8 port	10 port	12 port
Position A (Load)					
Position B (Inject)					
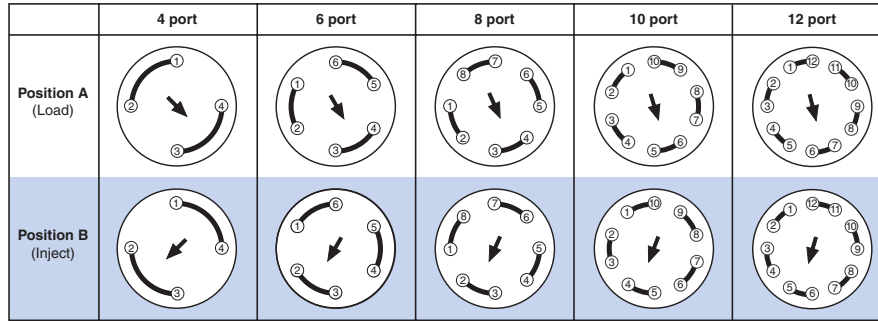
Table 1:
Time to required
to switch A to B
(or B to A)

Single stage		Dual stage	
4 pos.	155 ms	**6 pos.**	347 ms
6 pos.	118 ms	**8 pos.**	307 ms
8 pos.	104 ms	**10 pos.**	279 ms
10 pos.	91 ms	**12 pos.**	231 ms

Note: On power up, the actuator is ready to move from it current position to the opposite position. All move requests are valid only to the opposite position from the current position indicated.

Installation

Mounting

Mount the unit in a horizontal position. Avoid any orientation that positions the control board on the bottom, where it could be damaged by leakage. Mounting hole locations are shown in **Figure 1**. There are four 4-40 tapped mounting holes on the valve face of the gearbox and another four on the side of the gear housing. NOTE: 8 and 10 port valves with 1/4-28 fittings have larger bodies which block the mounting holes on the valve face, as highlighted in the red box of **Figure 1**.

Electrical Connections

Cables for electrical connections can either be ordered from VICI or constructed in-house. To order from VICI, request product numbers I-25176 for the I/O control cable and I-24780 for the power cable.

If you prefer to make your own cables for I/O control and power:

1. Use a Molex 26-03-4020 shell and 08-58-0111 contacts with 22 awg stranded wire to supply 24 volt current (3 amps recommended) to the connector marked J1. *(See **Figure 3**.)* The motor can draw as much as 2.5 amps during movement so make sure there is adequate power available, and do not share power with other sensitive circuits.

2. Use an Amphenol 65846-015LF shell and 47715-000LF contacts to make the connection to Connector J3, which provides the contact closure input and detects the output of the position sensor. *(See **Figure 4** and **Table 2**.)*

    Position feedback is obtained from the A and outputs shown in **Figure 4**. These are 5 volt tolerant, 3 volt logic outputs, sourcing and sinking a maximum of 20 milliamperes each. An output will go high (+3V) when the valve reaches the respective position.

Caution:

Do not attempt to source or sink more than 20 mA from either output.

24 VDC (±1)
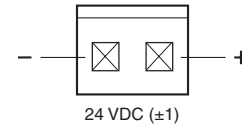
Figure 3:
Power connector J1, pin view

A OUTPUT (+3 V)   B OUTPUT (+3V)
A CONTACT   B CONTACT
COMMON
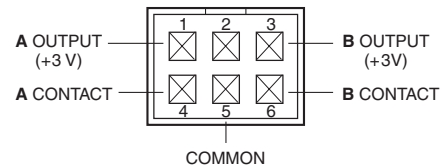
Figure 4:
Control connector J3, pin view

Pin #	Color	Function
1	Green	A output (3.3 VDC)
2		Unused
3	White	B output (3.3 VDC)
4	Black	A contact
5	Shield	Common
6	Red	B contact

Table 2: Connector J3
pin assignments
(Colors are in reference to
VICI cable I-25176)

Motor Control Modes

Single Contact Closure Control *(default)*
In this mode, applying and maintaining a connection between the common and "B contact" pins keeps the injector in the load position (A). Releasing the contact returns the injector to the inject position (B). This logic permits position B (inject) to be the default position – that is, the state the injector will be when the instrument power is off.

Dual Contact Closure Control
In this mode, holding a contact closure (50 msec minimum) between the "A contact" and common on connector J3 moves the injector to position A (inject). The injector does not move when the contact closure is released. Likewise, providing a contact between the "B contact" and common moves the injector to the B (load) position. Contact closures must be released before the opposite closure can be applied. To change the actuator to this mode, see instructions in the next section.

| Control Mode	Valve Movement	Contact	
		A	B
Single contact closure	Load to Inject	X	0
	Inject to Load	X	1
Dual contact closure	None	1	1
	B to A	1	0
	A to B	0	1
	None	0	0

Table 3: Control logic
"1" indicates contact closure to common;
"X" indicates ignored

Jumper Settings

Factory-set jumpers determine the actuator motor's control mode (single contact closure) and proper angle of rotation (a function of the number of ports in the valve head).

Figure 5 shows the jumper location, with a jumper installed at position 1. *Jumper 4 must remain empty in two position applications.* (For multiposition applications, refer to Technical Note 821.)

A verbal presentation of the configuration information begins below. For a graphic presentation of the decision process, refer to **Figure 7**.
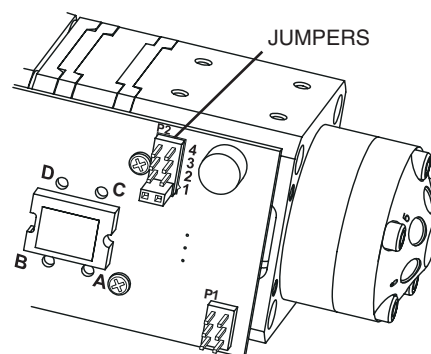
Figure 5: Location of jumpers

Setting the Motor Control Mode

Jumper 1 sets the control mode. When shipped from the factory, the mode is set to single contact closure control (no jumper installed). To change the control mode to dual contact closure:

1. Interrupt power to the motor by detaching power connector J1.

2. Install a jumper on the pair of pins at position 1, as shown in **Table 4**.

3. Re-attach connector J1. The change takes effect when the motor is powered up.

Control Mode	Jumper 1
Single contact	No
Dual contact	Yes

Table 4: Control mode jumper settings

To change back to single contact closure control, follow the same procedure but remove the jumper in Step 2.

Setting the Angle of Rotation

If you are changing the valve head to one with a different number of ports, jumpers 2 and 3 must be reconfigured. Remember that jumper 4 must remain empty for two position applications.

To set the motor for the proper amount of rotation:

1. Interrupt power to the motor by detaching power connector J1.

2. Refer to **Figure 1** to determine if the unit has a single stage gearbox or a dual stage gearbox.

3. Consult **Table 5** to determine the correct jumper arrangement, and install jumpers as indicated.

4. Re-attach connector J1. The change takes effect when the motor is powered up.

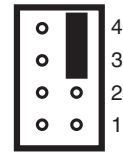| Single stage			Dual stage		
Jumper:	**2**	**3**	**Jumper:**	**2**	**3**
4 port	Yes	Yes	6 port	Yes	Yes
6 port	No	No	8 port	No	No
8 port	Yes	No	10 port	Yes	No
10 port	No	Yes	12 port	No	Yes

Table 5: Jumper settings for number of ports

Restoring the Default Baud Rate

To restore the baud rate to the factory default of 9600:
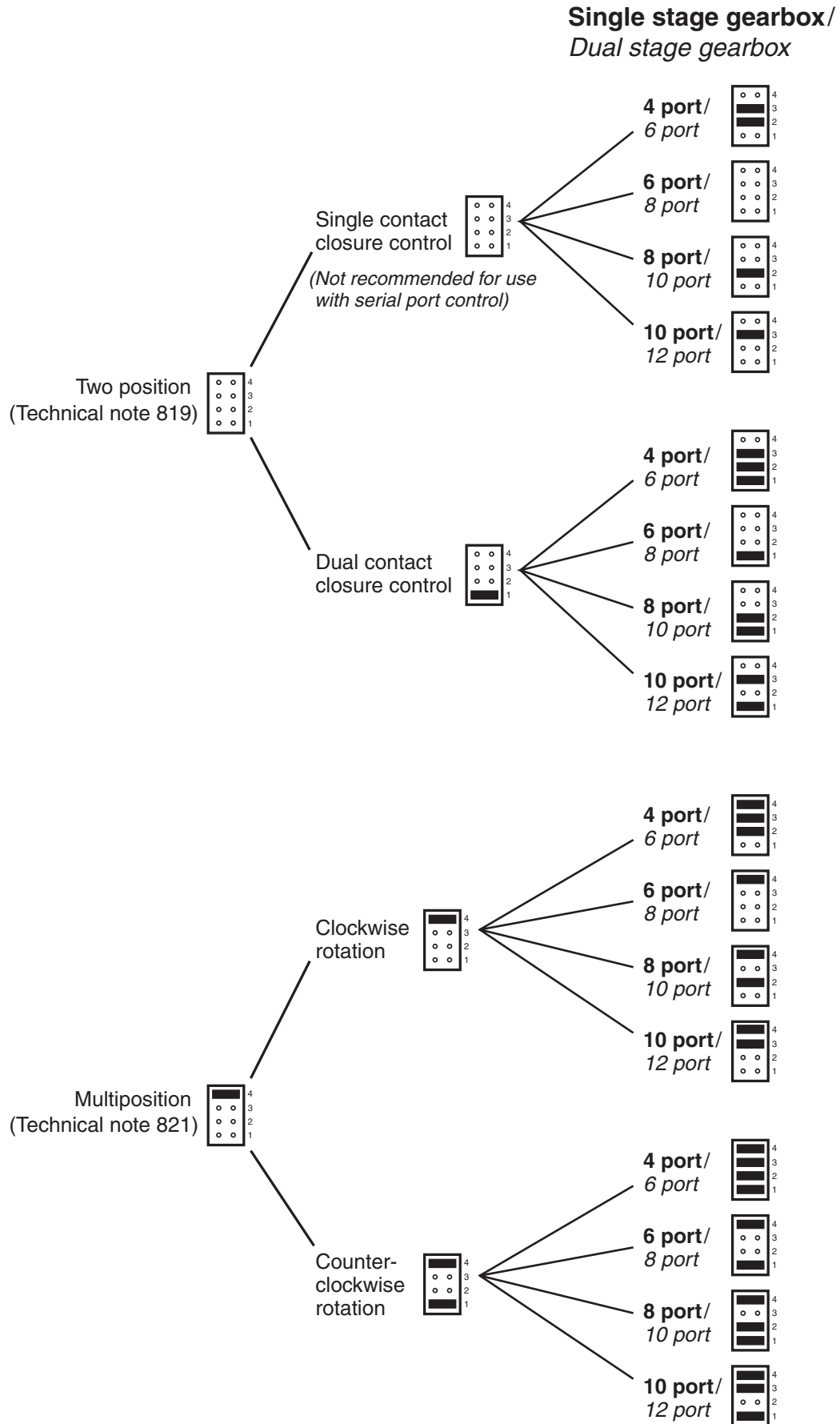
1. Interrupt power to the motor by detaching power connector J1.

2. Remove jumpers 3 and 4, noting their location for proper reinstallation.

3. Install a jumper as shown in **Figure 6**.

4. Re-attach connector J1. The rate change takes effect when the motor is powered up.

5. Detach power connector J1 and restore jumpers 3 and 4 to their previous configuration.

6. Re-attach connector J1.

Figure 6: Jumper position to restore default baud rate

Single stage gearbox/
Dual stage gearbox

4 port/
6 port

6 port/
8 port

Single contact
closure control

*(Not recommended for use
with serial port control)*

8 port/
10 port

10 port/
12 port

Two position
(Technical note 819)

4 port/
6 port

6 port/
8 port

Dual contact
closure control

8 port/
10 port

10 port/
12 port

4 port/
6 port

6 port/
8 port

Clockwise
rotation

8 port/
10 port

10 port/
12 port

Multiposition
(Technical note 821)

4 port/
6 port

6 port/
8 port

Counter-
clockwise
rotation

8 port/
10 port

10 port/
12 port

Figure 7: Decision tree for setting jumpers.
NOTE: The gearbox type is sensed automatically. For a visual determination, refer to **Figure 1**.

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Actuators with Optional Serial Control *(must be specified at time of purchase)*

RS-232 and RS-485 communication require a terminal emulation program. There are many emulators available for free on the internet. Though the programs vary, in general you will select "Serial" from among various types of connections, select the COM port which will be used, name the connection, and set the port baud rate as shown in **Table 7** (9600, or 9K60, is the factory default). The rest of the configurations are fixed at no parity, 8 data bits, 1 stop bit, no hardware or software handshaking.

A three-pin connector is used for the serial interface: pin assignments are listed in the table at right. Use VICI cable I-22697 or make your own with the parts named below the table. The implementation of RS-485 is half-duplex two wire with ground, and uses the same 3 pin output connector as RS-232.

With the software running, check the communication link between the computer and the serial port by typing **/?**<enter>. If the link is functioning, the menu below will appear on your monitor:

| Pin #	RS-232	RS-485
1	Ground	Ground
2	Transmit to host	A (–)
3	Receive from host	B (+)

Requires: Amphenol shell 102241
Amphenol pins 187756-1
or VICI cable I-22697

Table 6: Pin assignmentss

Control Command List

GO[nn]   Move to nn position
CW[nn]   Move Clockwise to nn Position
CC[nn]   Move Counter Clockwise to nn Position
CP   Returns Current Position
SB[nnnnn]   Set the Baud Rate to nnnnn
VR   Firmware Version
/?   Displays This List
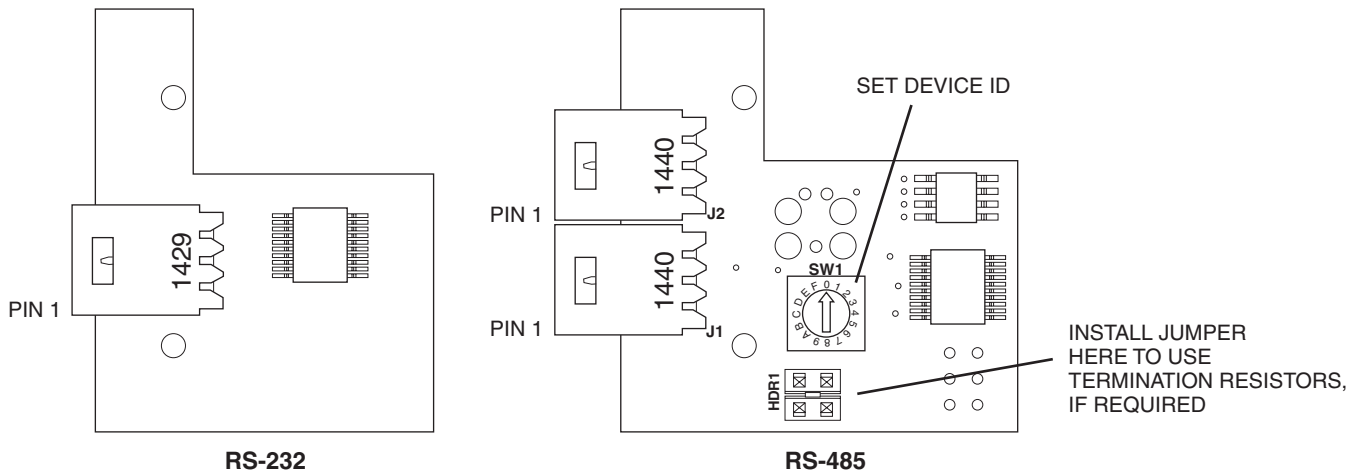
Figure 8: Serial boards

Serial Commands	
CCn	Sends the actuator counterclockwise to position n, where n is A or B
CP	Displays the current position
CWn	Sends the actuator clockwise to position n, where n is A or B
DTn	Display/set an inject delay interval (n seconds before the actuator returns to previous position)
E+/E-	Enable/disable the terminal echo and prompt (not available for RS-485)
GOn	Sends the actuator to Position n, where n is A or B
IC+/IC-	Enable/disable the invalid command response
LF+/LF-	Add/remove line feed to serial string, output only (not available for RS-485)
MD	Displays the unit model number
QS+/QS-	Enable/disable quiet serial output during startup (not available for RS-485)
R+/R-	Enable/disable position reporting
RC	Report the valve configuration
SB	Displays the current baud rate
SBnnnn	Sets the baud rate. Refer to the table below for nnnn values.
SN	Displays the unit serial number
TO	Sends the actuator to the opposite position (ignored in single contact closure mode)
TT	Sends the actuator to the opposite position, delays, and returns to original position (ignored in dual contact closure mode)
VR	Displays the part number and date of the firmware
/?	Displays a list of valid commands

Table 7: Commands and descriptions

Serial Communication Protocol

Serial communication is based on an ASCII string protocol. Carriage Return (OD hex) characters parse the communications by defining the end of each command. Software flow control (Xon/Xoff) and hardware handshaking are not supported. **Table 7** describes and explains all the commands available. A couple of simple examples are provided below.

CP   Displays the current position of the actuator
     Example
     Command: **CP**<enter>
               Returns (via the serial port) the current position, either A or B

Baud rate	nnnn
4800	4K80
9600	9K60
19200	19K2
38400	38K4
57600	57K6
115200	115K

SB [nnnn]   Sets the baud rate, where
     nnnn = a value from the table at right
     Example
     Command: **SB19K2**<enter>
               Sets the baud rate to 19200

Table 8: Baud rate values

Additional Information on the RS-485 Option

Hardware Protocol

The RS-485 hardware protocol is half-duplex implementation – two wires with a ground. There are two connectors which are connected in parallel to allow easy daisy chaining of multiple devices.

Hardware Termination

The RS-485 port on the host computer or controlling device generally includes terminating resistors, so on short cables no termination is required. However, if many devices are attached and/or the actuator is on the end of a long communication cable, the termination jumpers on the furthest device from the master RS-485 controller should have termination enabled. To use termination resistors, install a jumper on the header labeled HDR1, oriented as shown in **Figure 8** on page 6.

Hardware ID Set

The firmware requires a serially-addressed ID, which on this board is set by the 16 position rotary switch labeled SW1. The ID is set either as a number from 0 - 9 or a letter from A - F, as selected by the arrow on the face of SW1.

Software Protocol

The software protocol requires a forward slash [/] as a beginning-of-message character, followed by a single character ID. The end-of-message character which terminates the command is a <CR>. The standard RS-232 serial port commands are then supported within that protocol.

>   **Example:**
>   With the settings in **Figure 8**, the RS-232 command **VR**<enter> becomes **/0VR**<enter> in the RS-485 protocol; **/** is the start-of-message character, **0** is the current ID of the device, and **VR**<enter> is the command to be executed.

NOTE: Of the commands on listed on page 7, **E+/E-**, **LF+/LF-**, and **QS+/QS-** work only for RS-232; they are not available in RS-485 operation.

Cleaning and Rotor Replacement

These valves have polished sealing surfaces which must be protected during any disassembly or cleaning procedure. Work in a clean environment and always set parts on a soft tissue or clean paper. Cleaning a valve can often be accomplished by flushing all the lines with appropriate solvents. *Do not disassemble the valve unless system malfunction is definitely isolated to the valve.*
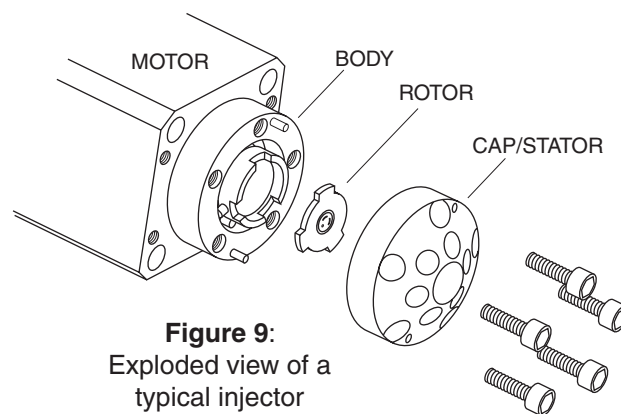
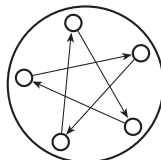**Figure 9**:
Exploded view of a
typical injector

Disassembly *(Refer to Figure 9)*

1. Use a 3/32" hex driver to remove the 5-40 socket head screws that secure the stator to the valve body. Alternate among the five screws in the sequence indicated in **Figure 10**, loosening them in quarter-turn (90°) increments until all load is removed.

2. To ensure that the sealing surface of the stator is not damaged, rest it on its outer face. Or, if the tubing is still connected, leave it suspended by the tubing.

3. With your fingers or a small tool, gently pry the rotor away from the driver.

4. Examine the rotor sealing surface for scratches. If you see any, the rotor should be replaced.

5. Examine the stator sealing surfaces. If scratches are visible between the ports, that part should be replaced or resurfaced. Call VICI for help in determining if resurfacing is feasible.

6. Clean all the parts thoroughly with an appropriate solvent, taking care that no surfaces get scratched. (A common problem with HPLC is the formation of buffer crystals, which are usually water-soluble.) It is not necessary to dry the rotor.

Reassembly

1. Replace the rotor in the driver, making sure that the rotor sealing surface with its engraved flow passages is facing out. The tabs on the rotor have an asymmetrical pattern to prevent assembly with improper orientation.

2. Replace the stator. Insert the five socket head screws and tighten them gently until they start to get snug. Alternate among the five screws in the sequence indicated in **Figure 10**, tightening them in quarter-turn (90°) increments until the stator is flush against the valve body.

   Do not overtighten the screws – they simply hold the assembly together and do not affect the sealing force, which is automatically set as the screws pull the stator against the valve body.

3. Test the valve by pressurizing the system. If it doesn't hold pressure, the valve should be returned to Valco for repair.

Figure 10:
Loosening and tighening order