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Porous membrane tubular supports for solid phase synthesis. Immobilization of carboxyl-terminated polypeptides on membrane supports under solid phase synthesis conditions is described. These include high density, low crosslinking, polymeric membranes (polysulphone, Nylon, PVC), porous glass, and an acrylonitrile-fumarate porous membrane. Various coupling chemistries are compared in order to assess the influence of membrane properties on coupling efficiencies. We find that the fumarate-containing membrane is a unique membrane in which coupling does not occur because of the carboxyl-termination. Both the Nylon and PVC polymers exhibit low (less than 2%) coupling efficiencies at elevated temperatures (100 degrees C). The other membranes (polysulphone, glass) exhibit efficiencies between 5 and 25%. Excellent coupling efficiencies (55 to 85%) are obtained with polysulphone membrane at 50 degrees C. The coupling procedure is generally more convenient with the polysulphone than with the other membranes. The combination of solid phase synthesis and membrane technology has resulted in a versatile method of solid phase synthesis that has many potential applications.

A robot is a programmable, mechanical device that can be instructed to perform a series of tasks in a repeatable fashion. There are many different types of robots, but they can be generally categorized as either "nonsmart" robots or "smart" robots. A nonsmart robot is one that has no ability to make decisions. It can be instructed to carry out a specific task by a human operator, but it cannot make decisions about the task, such as when to initiate an action, when to continue an action, or how to change its direction or speed. The operator controls the nonsmart robot by providing it with specific instructions. A smart robot on the other hand is one that is capable of making decisions. Unlike a nonsmart robot, a smart robot can determine how to perform a task by analyzing its environment and making decisions based on those analyses. Some robotic systems use a vision system to perceive and analyze the environment of the robot and control

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