

ABSTRACT

A transfer robot includes a support (2), a fork (3), a flexible lifting member (43), and a lifting power assembly. The flexible lifting member (43) is wound around the support (2), and the lifting power assembly is connected with the flexible lifting member (43). The fork (3) is able to vertically move along the support (2). A first end of the flexible lifting member (43) is bypassed from a top part of the support (2) and connected with a top end of the fork (3), and a second end of the flexible lifting member (43) is bypassed from a bottom end of the support (2) and connected with the bottom part of the fork (3).

[Fig. 1]