

ABSTRACT

This application relates to a fork and a carrying robot. The fork (300) includes a telescopic arm, a temporary storage tray (320), and a sliding assembly (330). The telescopic arm includes a fixed arm (311), a movable arm (312), a pusher assembly (340), and a driving assembly. One end of the movable arm (312) is connected to the fixed arm (311), and an other end thereof is connected to the pusher assembly (340). The movable arm (312) is telescopically movable relative to the fixed arm (311) with an action of the driving assembly, and the pusher assembly (340) is configured to pull in or push out goods. The temporary storage tray (320) is mounted to the fixed arm (311) and is configured to temporarily store the goods. The sliding assembly (330) is mounted between the fixed arm (311) and the temporary storage tray (320) and is capable of pushing the temporary storage tray (320) to extend out relative to the fixed arm (311). An extending direction of the temporary storage tray (320) is consistent with an extending direction of the movable arm (312). According to the fork and the carrying robot of this application, the sliding assembly is capable of pushing the temporary storage tray (320) to extend out relative to the fixed arm (311). Therefore, when the fork of this application pulls in or pushes out the goods, containers can be stably carried between a stationary shelving unit and the temporary storage tray.

Fig. 2