

ABSTRACT

A robot arm for holding a cassette and an automatic cassette transfer device, comprising: a robot arm (1), an end actuator (2) provided at an end of the robot arm (1), and a visual positioning assembly (3) provided on the end actuator (2). On the one hand, the flange position of a cassette is positioned by means of the visual positioning assembly (3) so as to identify the cassette, that is, the identification is made on the basis of the characteristics of the cassette itself, without having to attach additional markings, thereby improving the accuracy of measurement and cassette grasping; on the other hand, the end actuator (2) holds a cassette and performs cassette transfer by means of a concave surface on the end actuator (2) which is adapted to a top flange of the cassette.