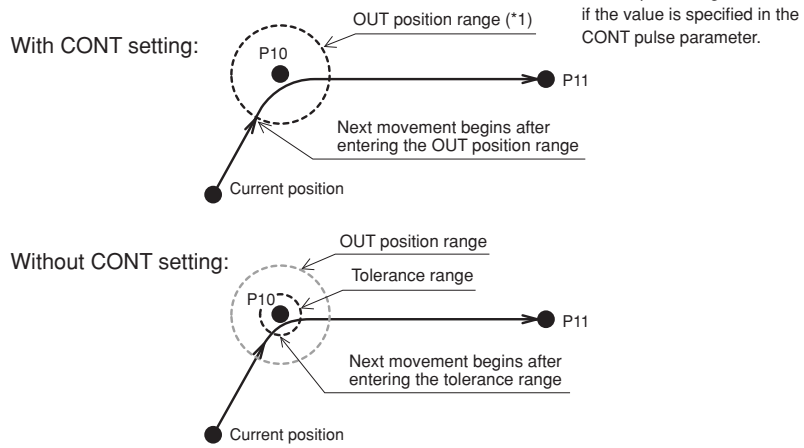


SAMPLE

```
MOVE P, P10, P11, CONT
```

.....Robot 1 Moves from the current position to the position specified by P10, and then moves to P11 without waiting for the moving axes to arrive in the tolerance range.

SAMPLE:MOVE P CONT



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SAMPLE

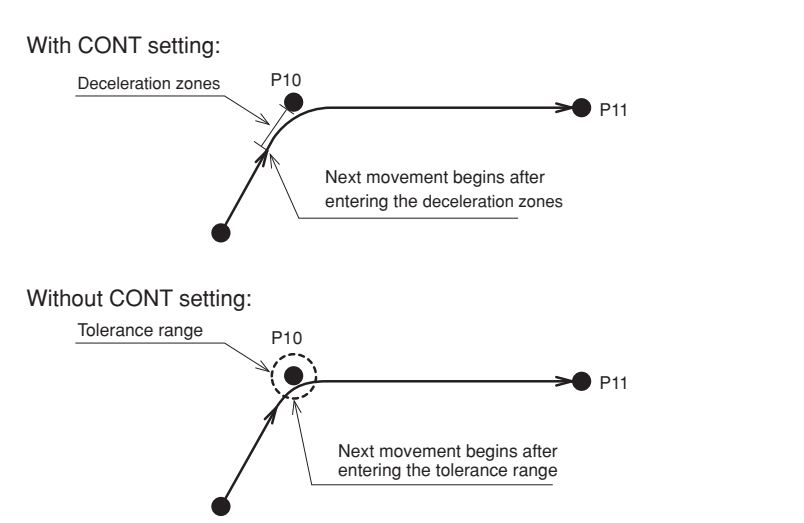
```
MOVE L, P10, CONT
MOVE L, P11
```

.....Robot 1 Moves from the current position to the position specified by P10, and then moves (linear interpolation movement) to P11 without waiting for the moving axes to arrive in the tolerance range, and completes the movement within the tolerance range.

MEMO

- The interpolation movement with CONT setting doesn't stop at intermediate points in the continuous movement.

SAMPLE:MOVE L CONT



33810-R9-00