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See also The Blackout Bold Beast Android Movie Recorder BoldBeast Recorder Call recorder Call recorder Call Recording Software Mute Whistler Alibabacom LG ALTLite 3 Blackout Video Recorder References Category:Video recording software Many previous attempts to use a robot to displace an operator or mechanized device in a production line have failed to realize the full potential because they have been unable to overcome the problem of “false” signals or “jumps” in the robot. Herein, the term “false signals” refers to signals generated in the robot when the robot hits a sensor, or vice versa, i.e., when the robot “hits” the surface of a work piece or the sensor. In a typical production line, there are two types of false signals. One type is where the robot is moving and hitting a sensor or work piece (or vice versa). In this case, the robot is actually operating and picking up work piece or performing a function that causes a false signal to be generated. The other type is when the robot is stationary and a work piece or sensor has moved past the robot, causing a false signal. Typically, if the robot is traveling in a radial direction, and a false signal is generated, the robot will stop, usually at a speed of zero, and then resume its previous direction, traveling at whatever speed. If the robot is in a non-radial direction, a false signal may cause the robot to reverse. Thus, in order to allow for continued robot operation, it is desirable to be able to distinguish a false signal from a true signal. Various robot trajectory control schemes have been proposed to deal with false signals. For example, U.S. Pat. No. 7,124,260 proposes a control scheme for keeping a robot moving in the same direction after a false signal, but stopping the robot if the false signal is followed by a true signal. However, when a robot uses such a scheme, a resulting trajectory may have a discontinuity in which the robot moves at an increased rate in one direction, and then in the opposite direction at a reduced rate. Alternatively, the robot may be slowed, without decelerating, after a false signal, thereby causing an increase in the time to complete a trajectory. Other control schemes have focused on adjusting a motion of a robot to avoid false signals. For example, U. 2d92ce491b