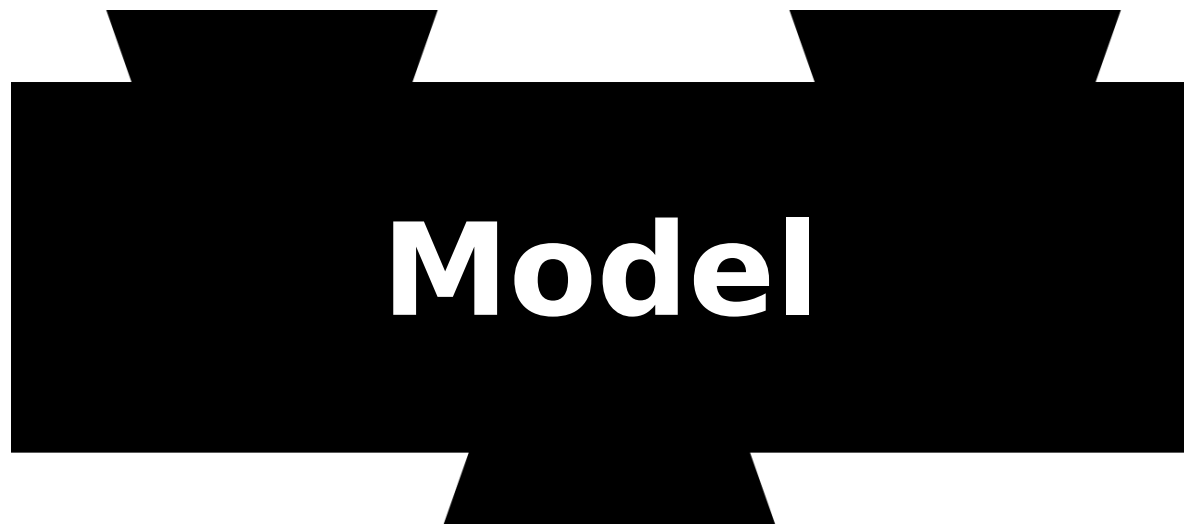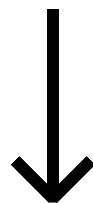**Control**

Model

Motion