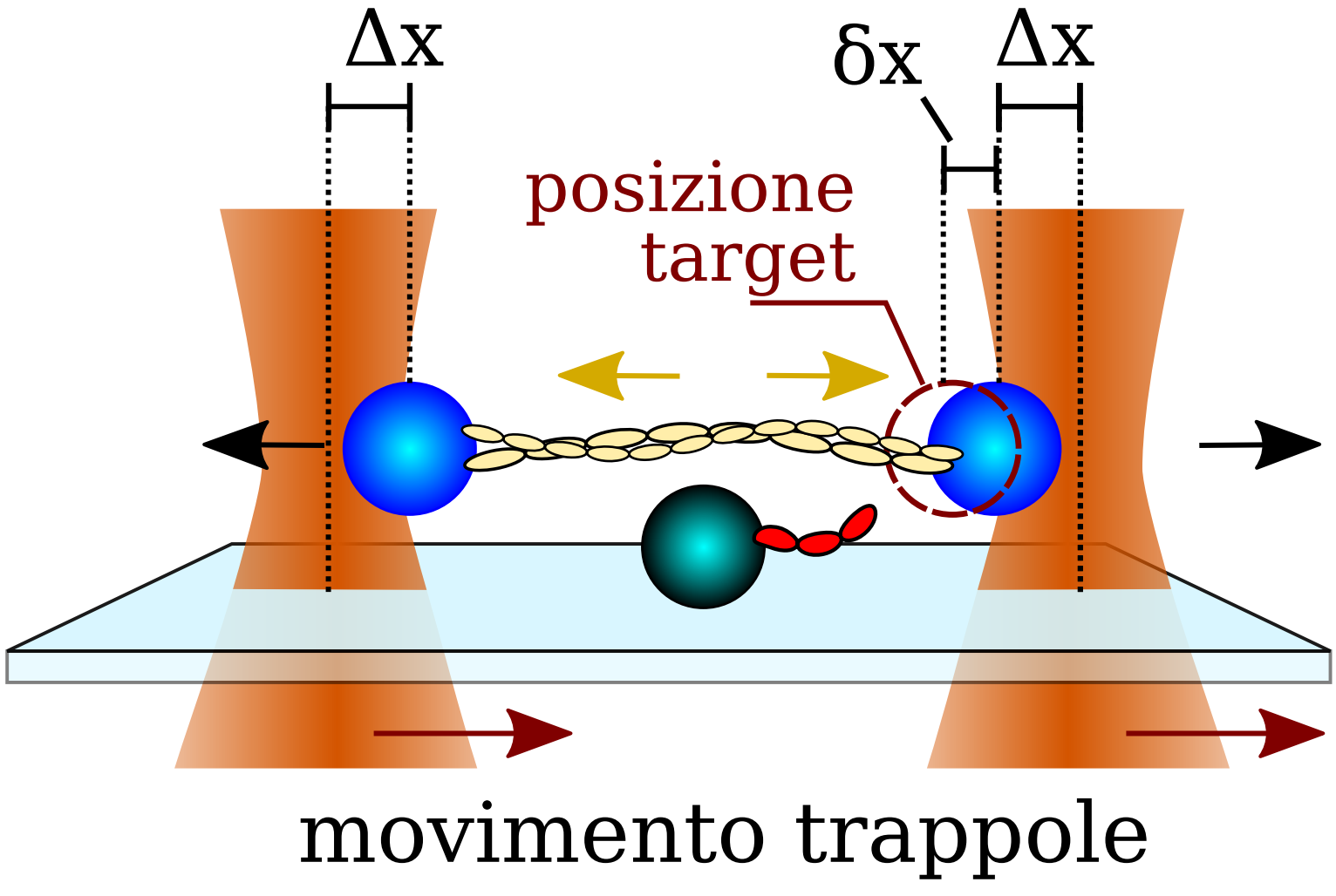
Δx
δx
Δx
posizione
target
movimento trappole