

# Continuum Robot PPO report

Model Name	./model/reward_f1
Time	2025-04-20 23:02
Model_Type	PPO
Timesteps	22000000
Control Mode	1
Device	cuda
Network Arch	[1024, 1024, 512]
Average Error	0.6042931394482478
batch	16384
buffer_size	100
train_freq	1
learning_starts	1
n_steps	2048
n_epochs	10
learning_rate	0.0003
n_env	48
best_value_loss	0.1611997328698635

## Reward Function Source

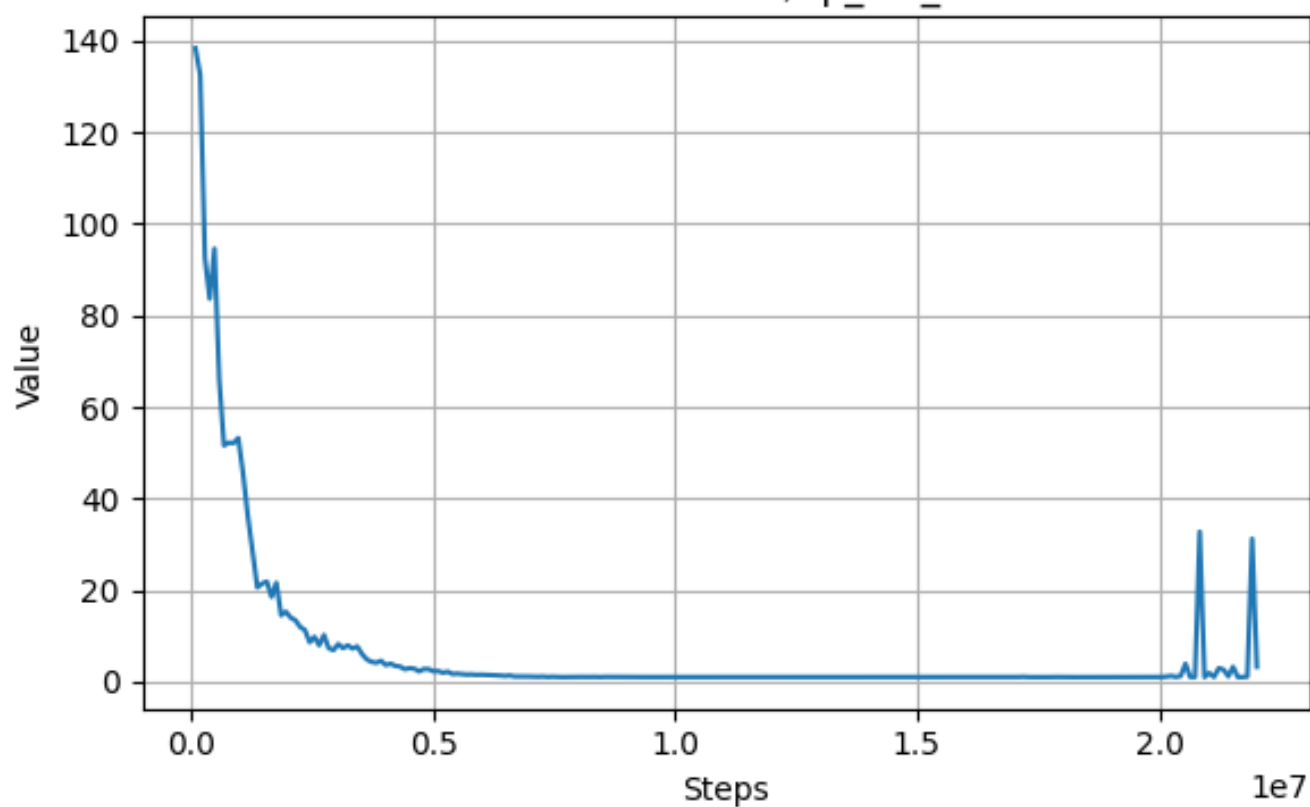
```
def my_custom_reward1(distance):  
    return -distance + np.exp(-distance**2) * 5
```

## Done Function Source

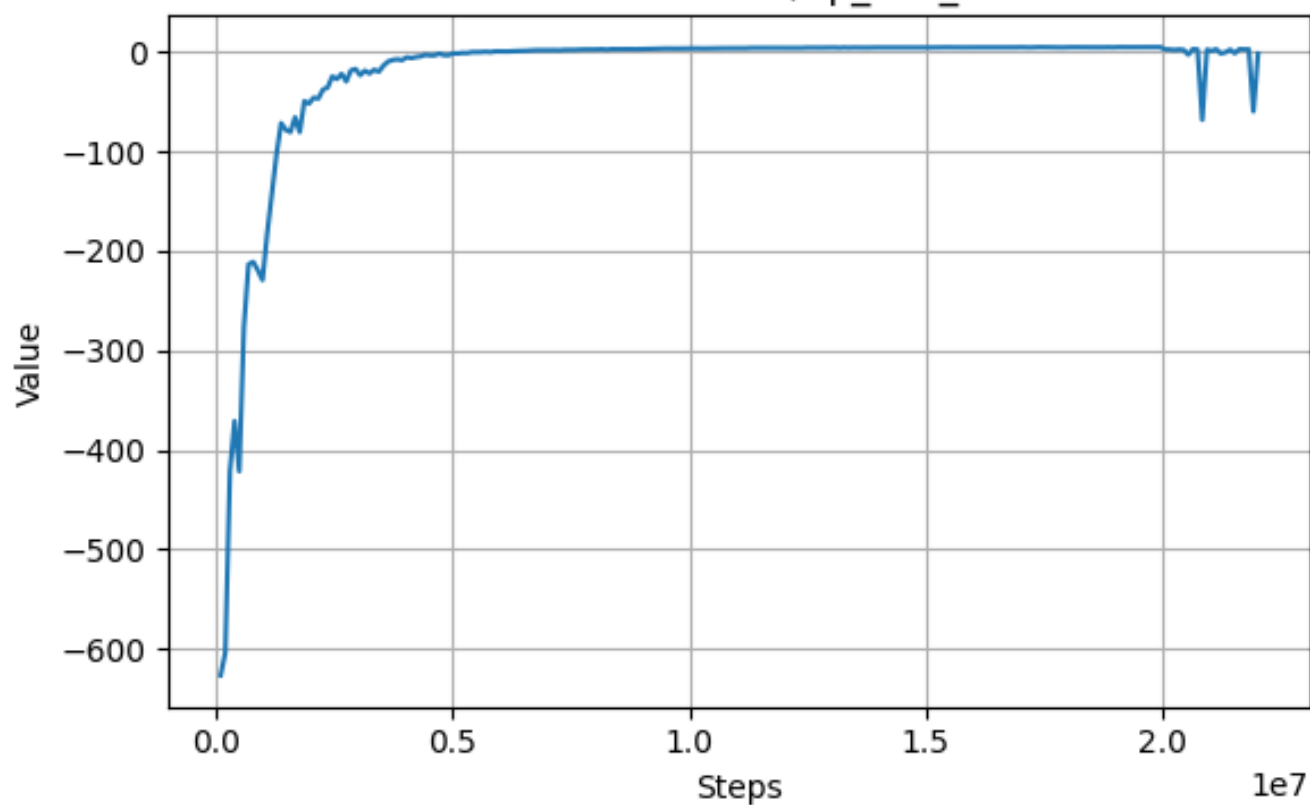
```
def my_custom_done3(reward, step):  
    return reward>-1
```

## Training Reward Curve

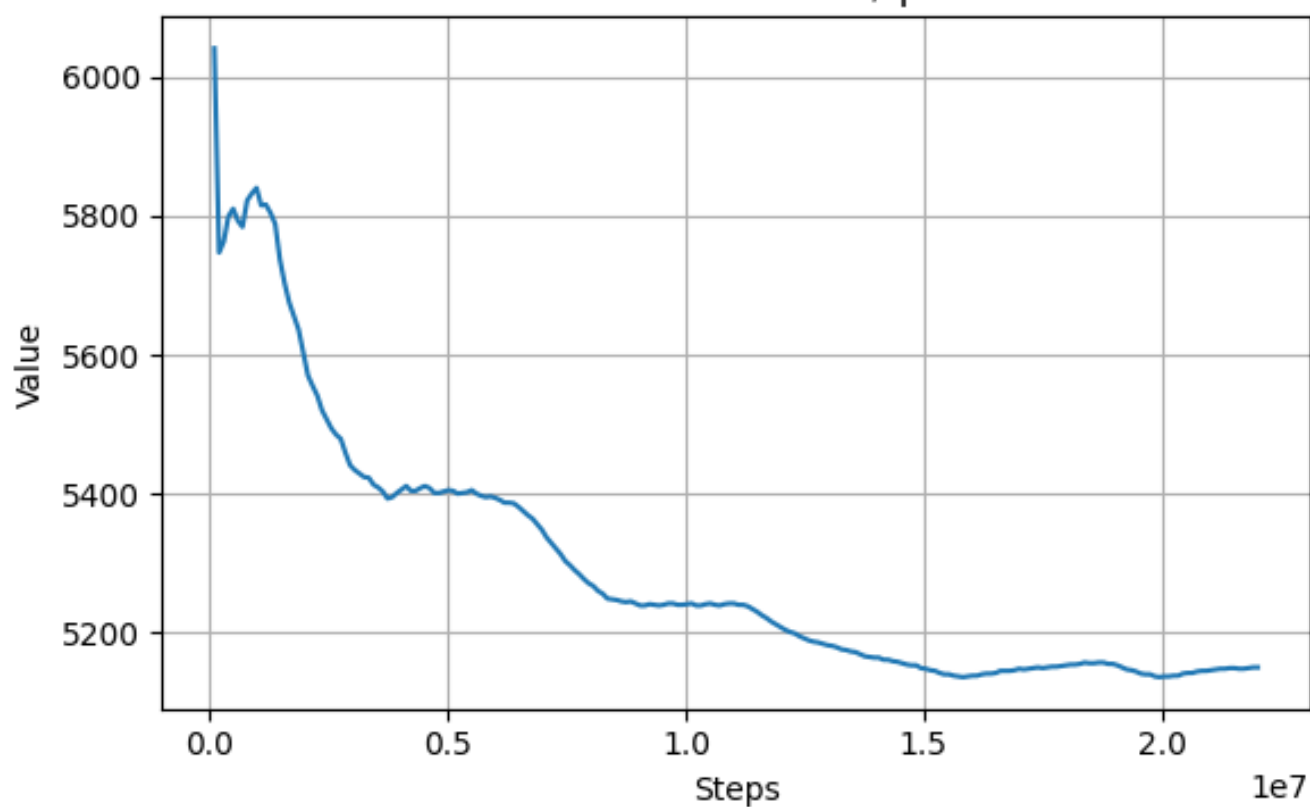
TensorBoard: rollout/ep\_len\_mean



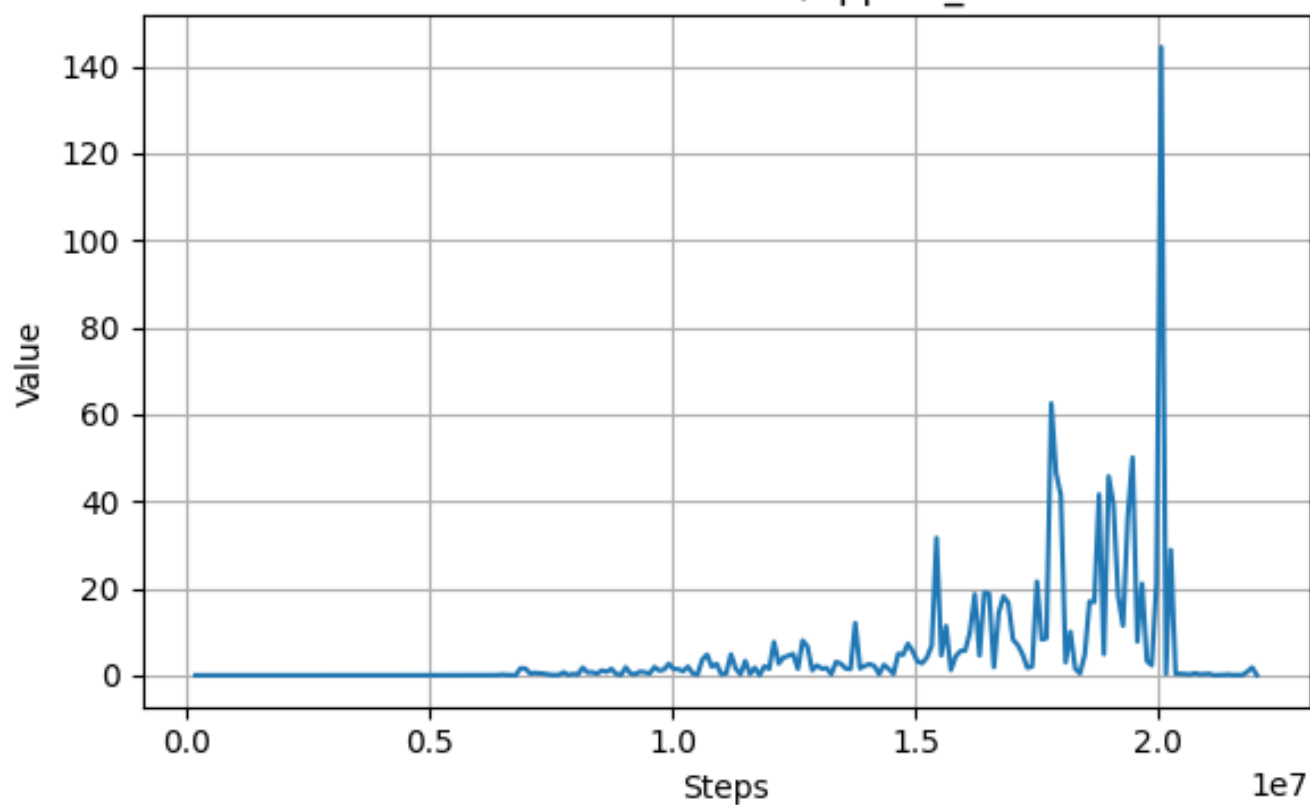
TensorBoard: rollout/ep\_rew\_mean



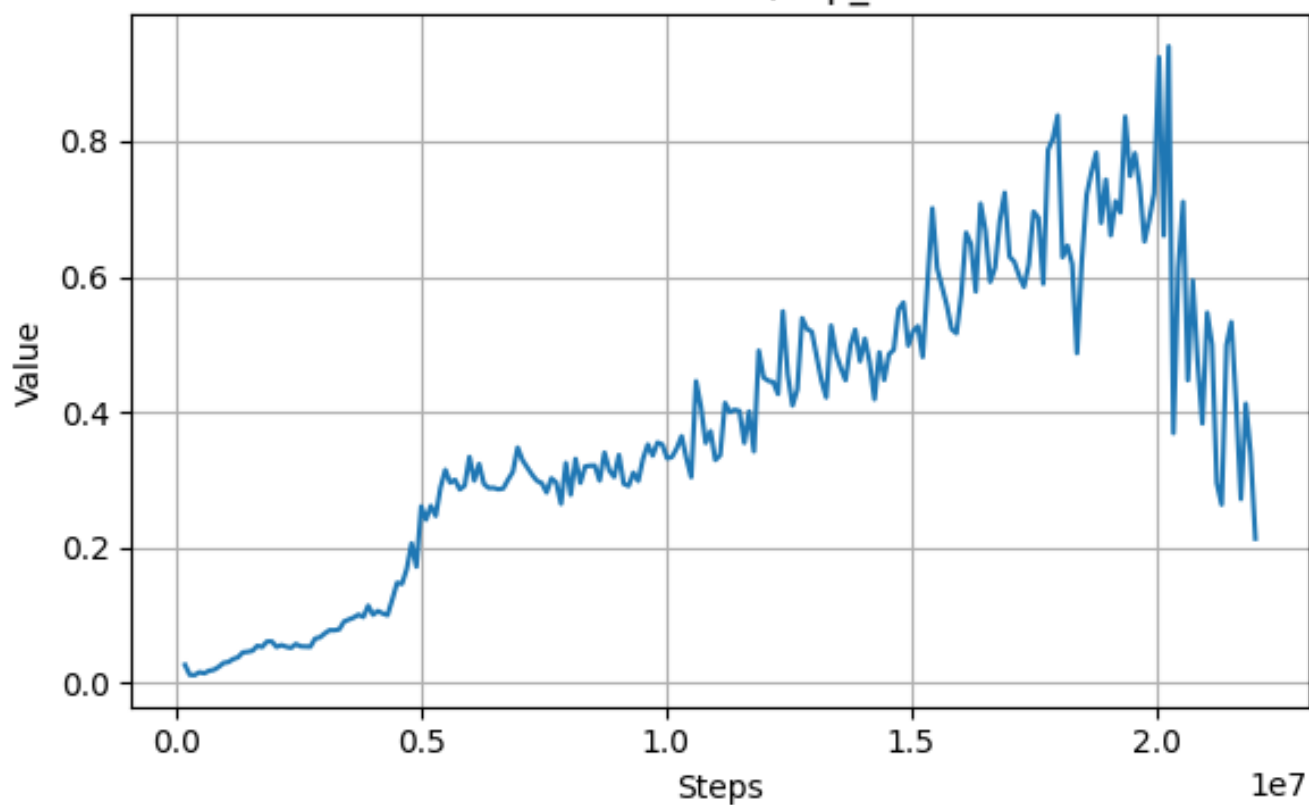
TensorBoard: time/fps



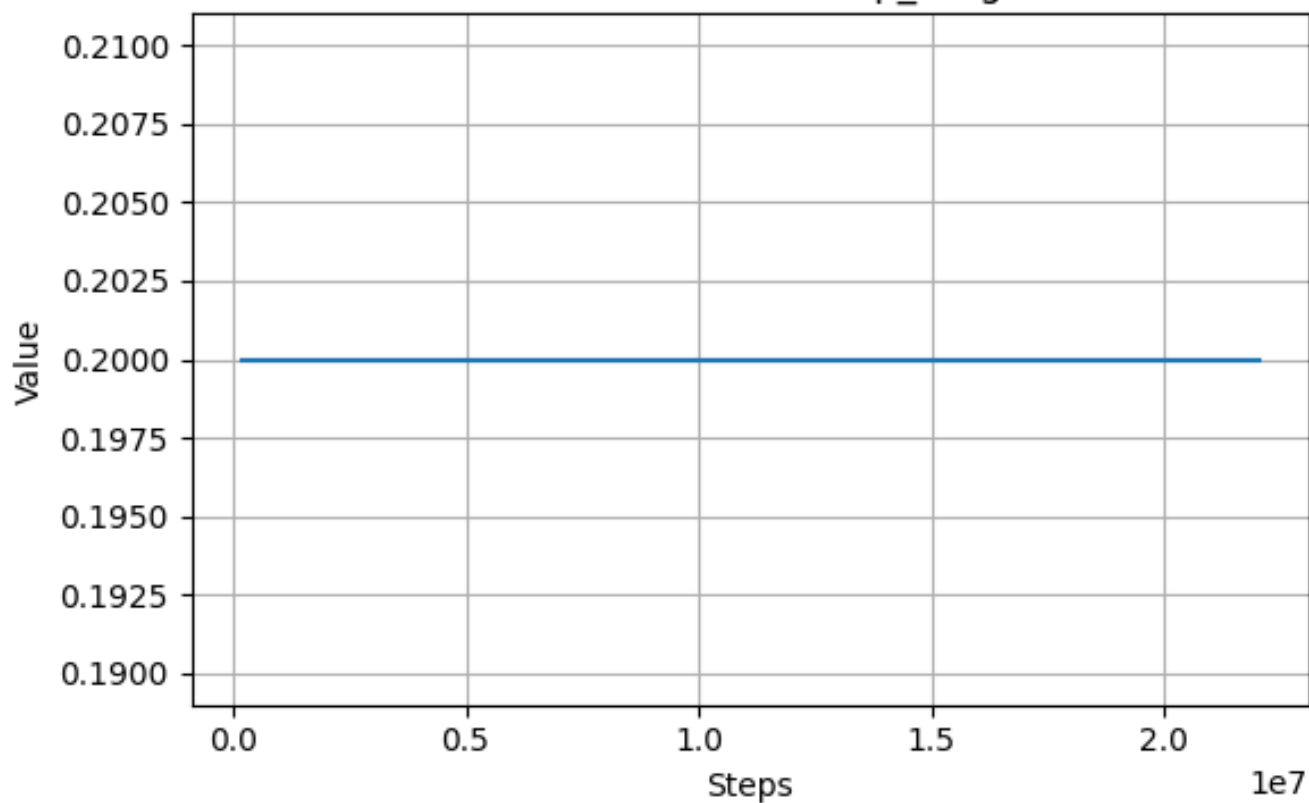
TensorBoard: train/approx\_kl



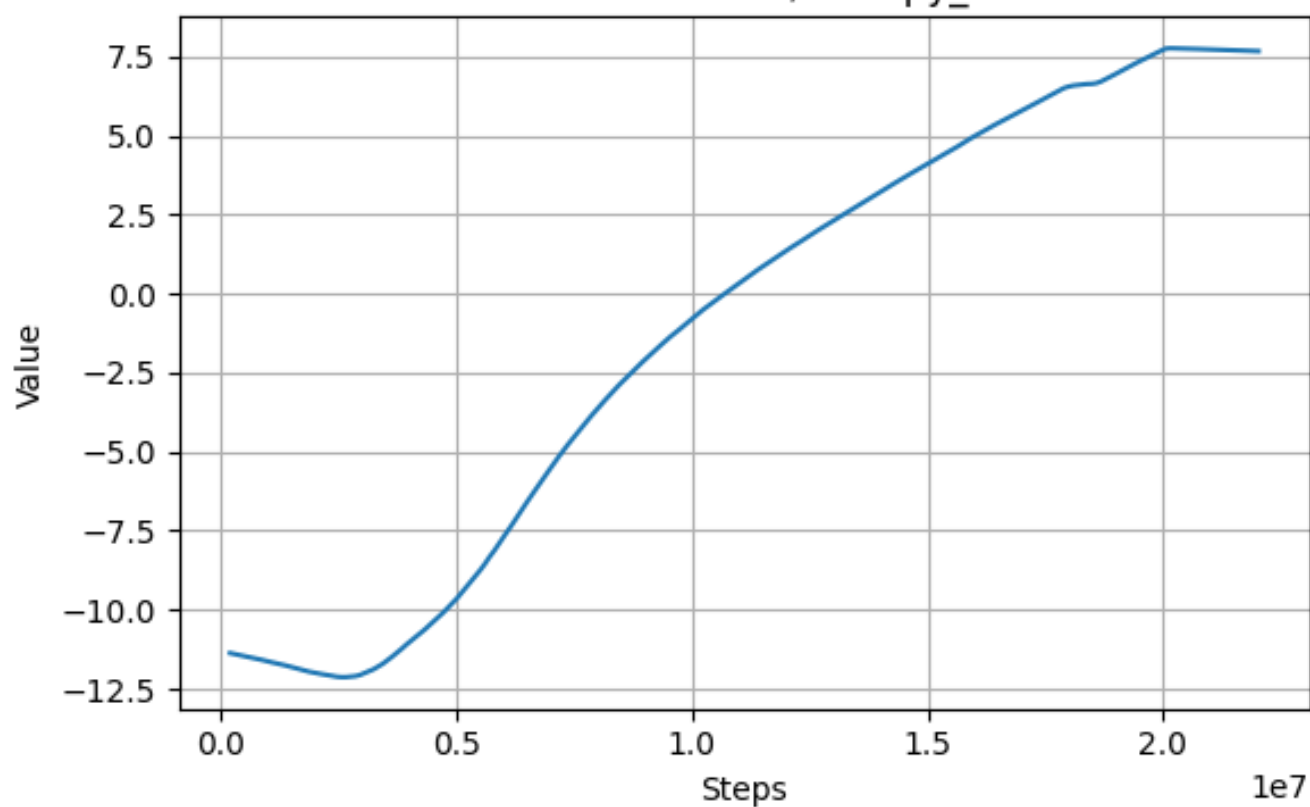
TensorBoard: train/clip\_fraction



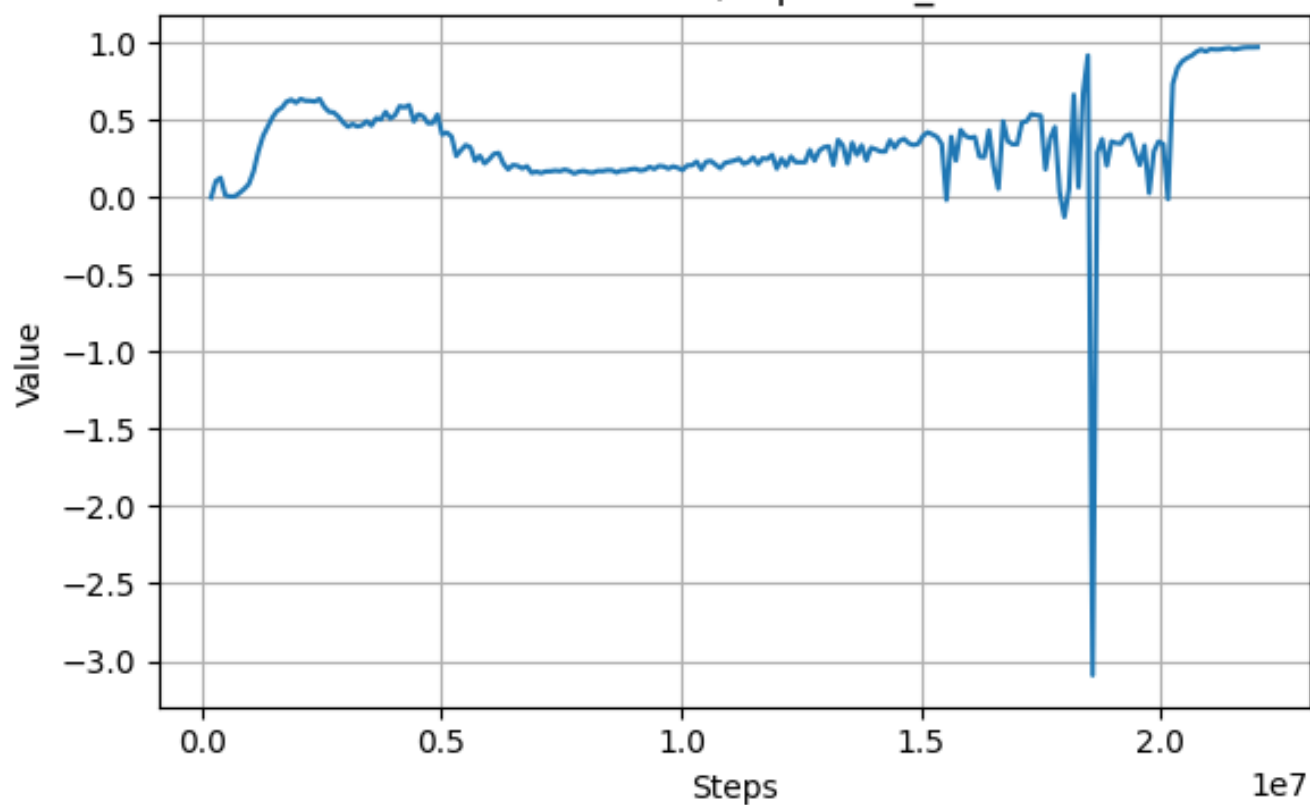
TensorBoard: train/clip\_range



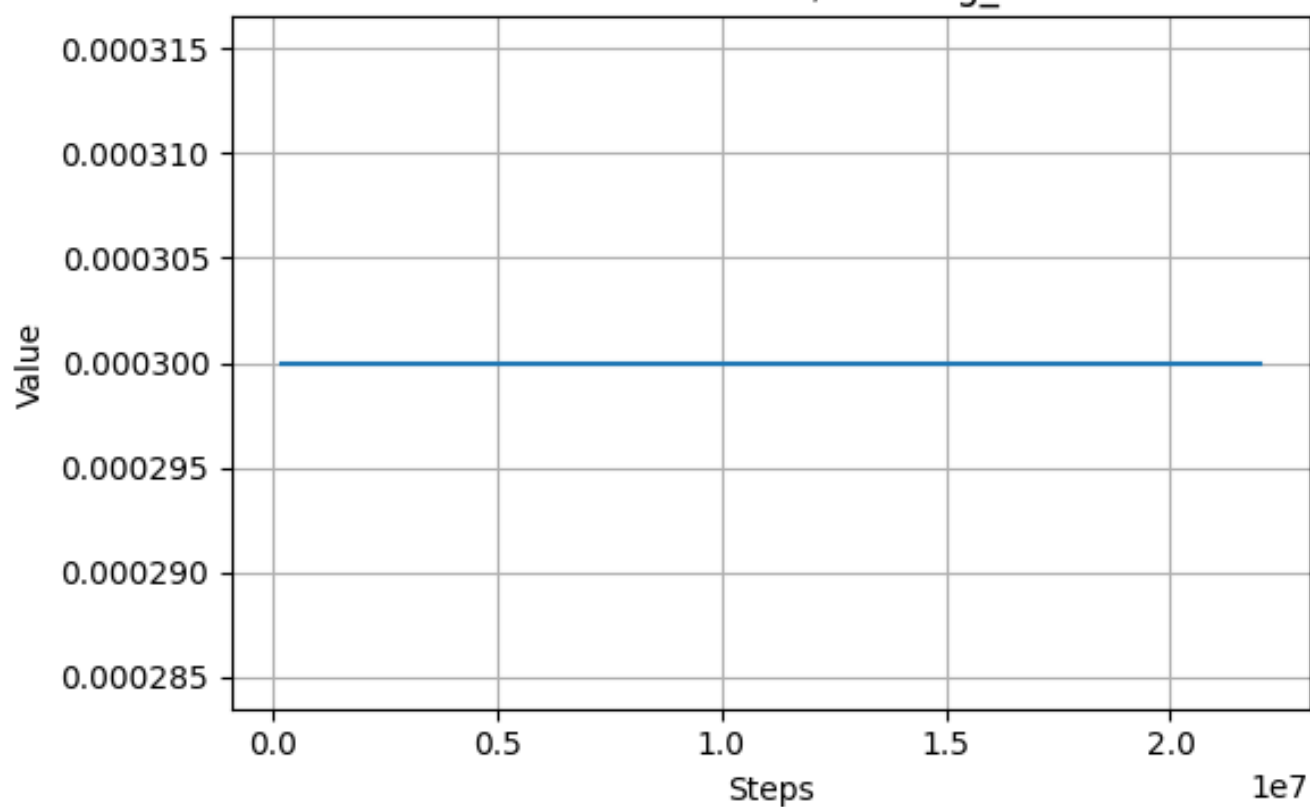
TensorBoard: train/entropy\_loss



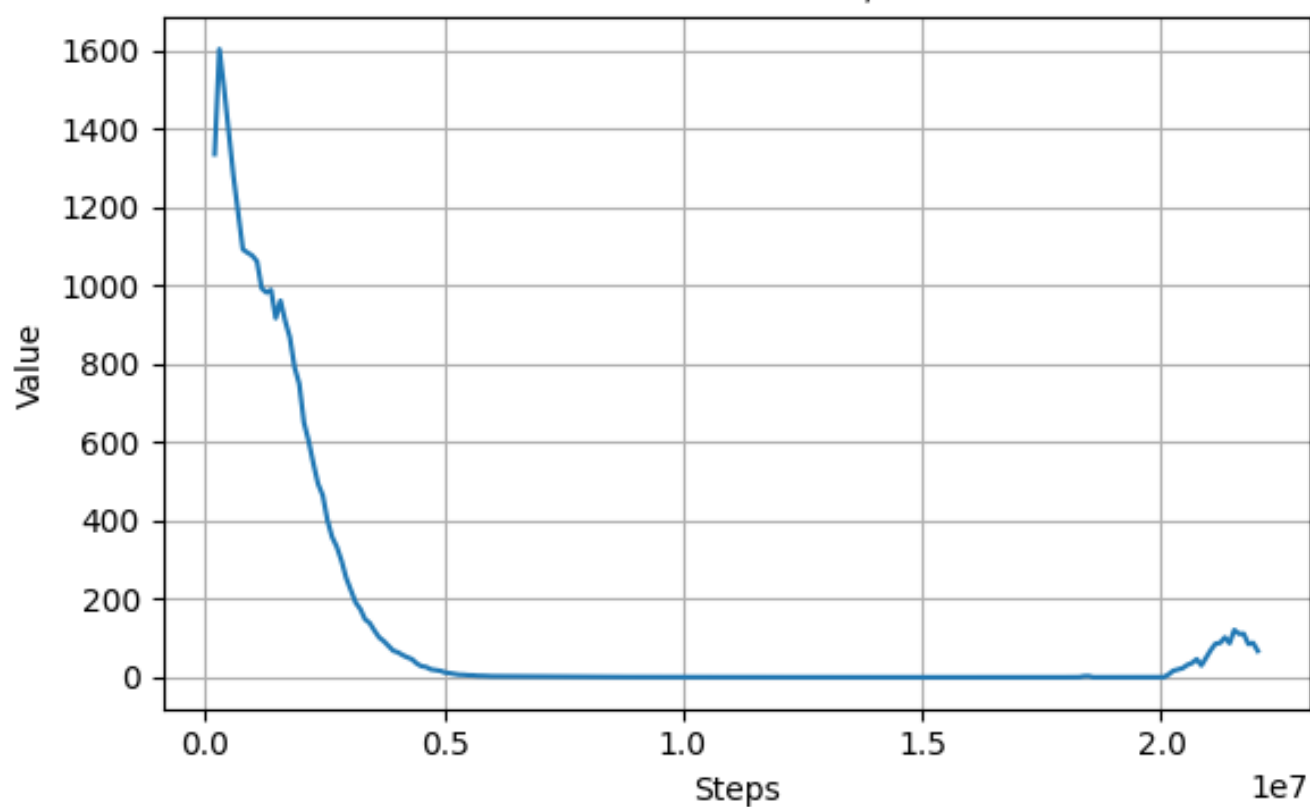
TensorBoard: train/explained\_variance



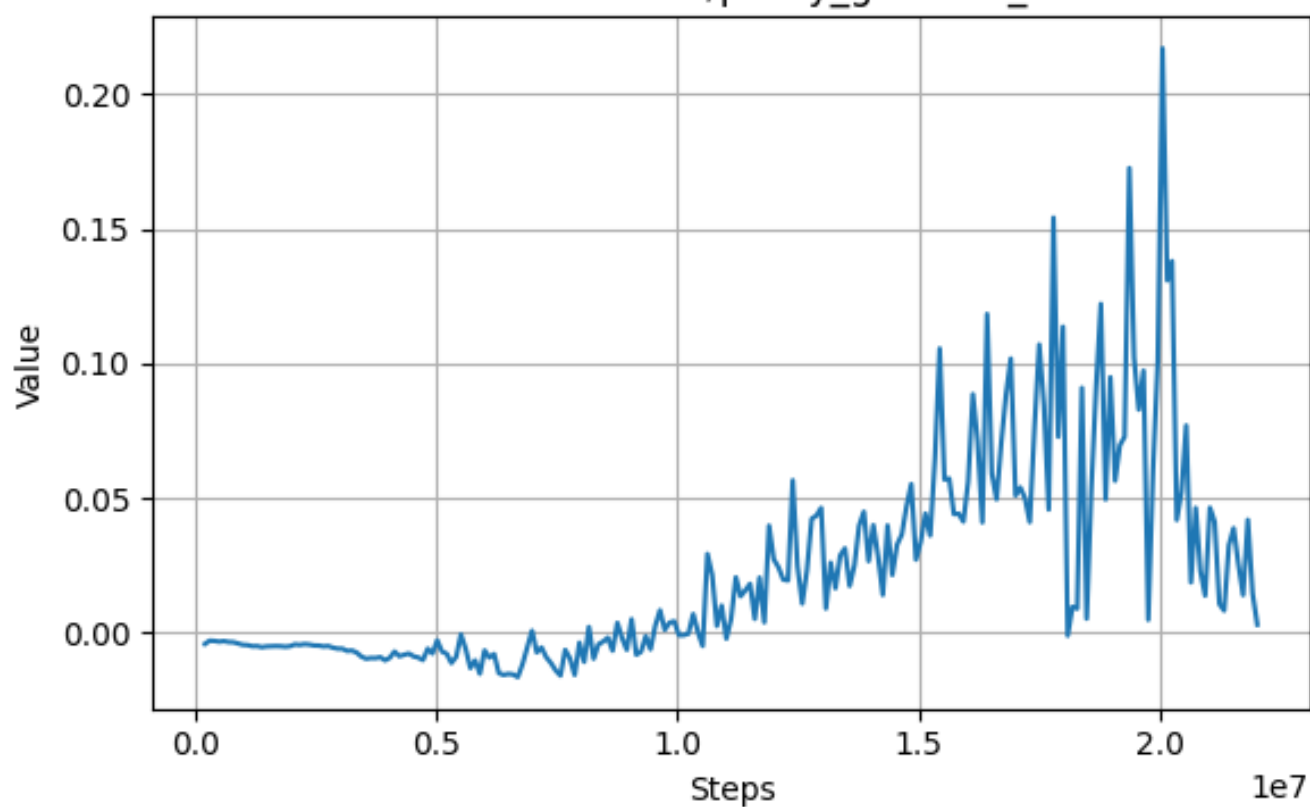
TensorBoard: train/learning\_rate



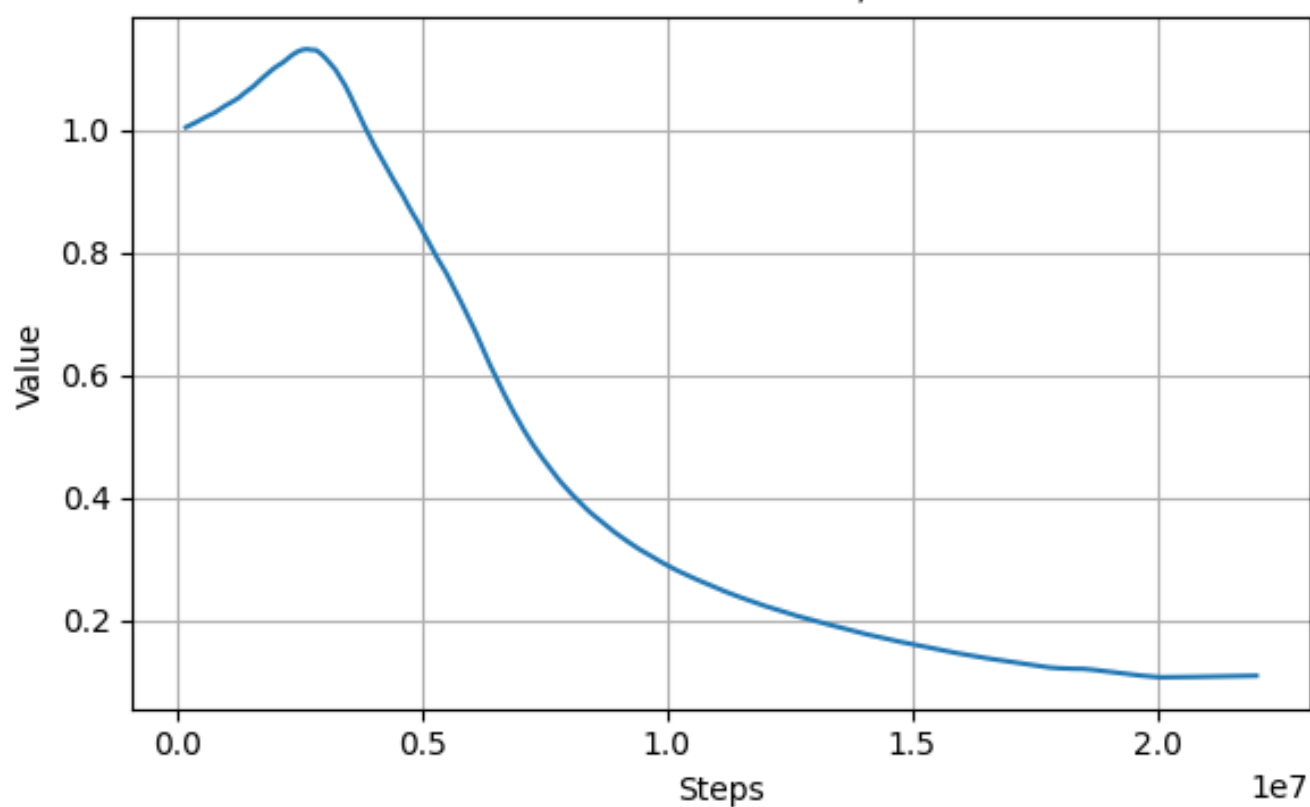
TensorBoard: train/loss



TensorBoard: train/policy\_gradient\_loss



TensorBoard: train/std



TensorBoard: train/value\_loss

