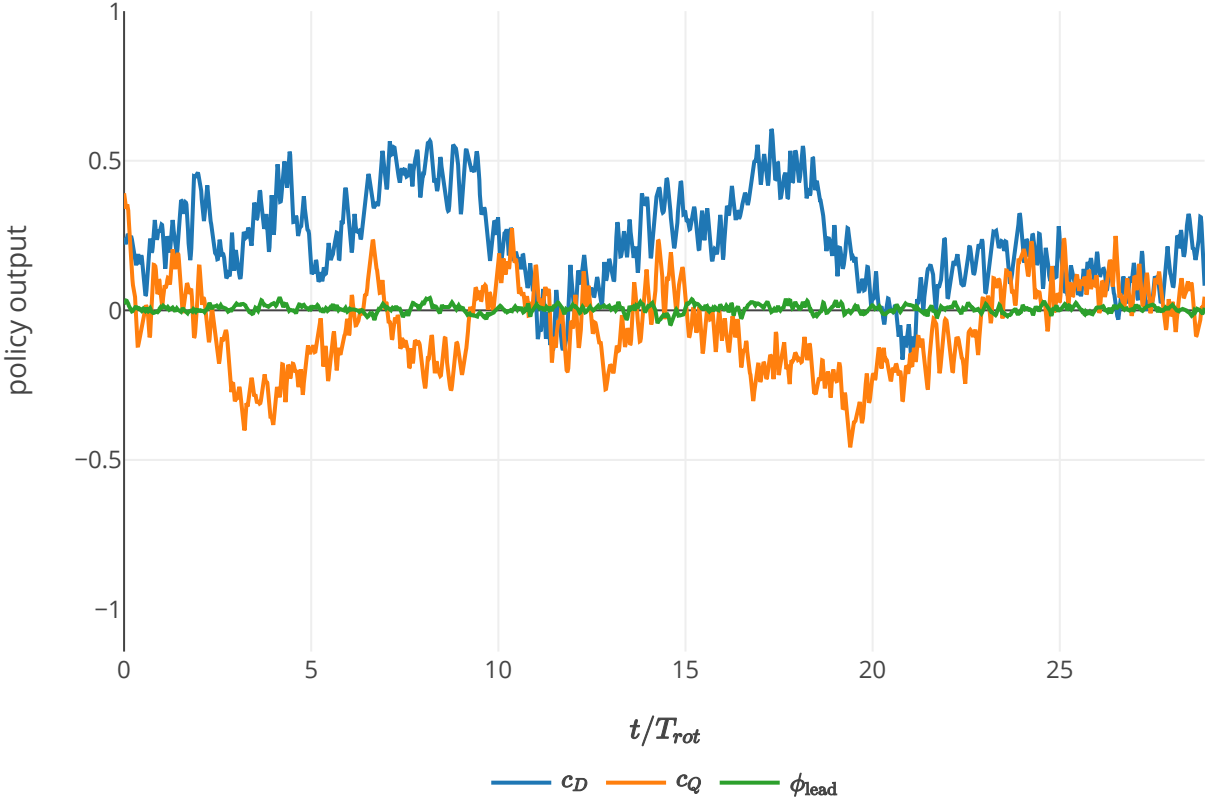
1
0.5
0
−0.5
−1
policy output
0
5
10
15
20
25
t/T_{rot}
c_D
c_Q
ϕ_{lead}