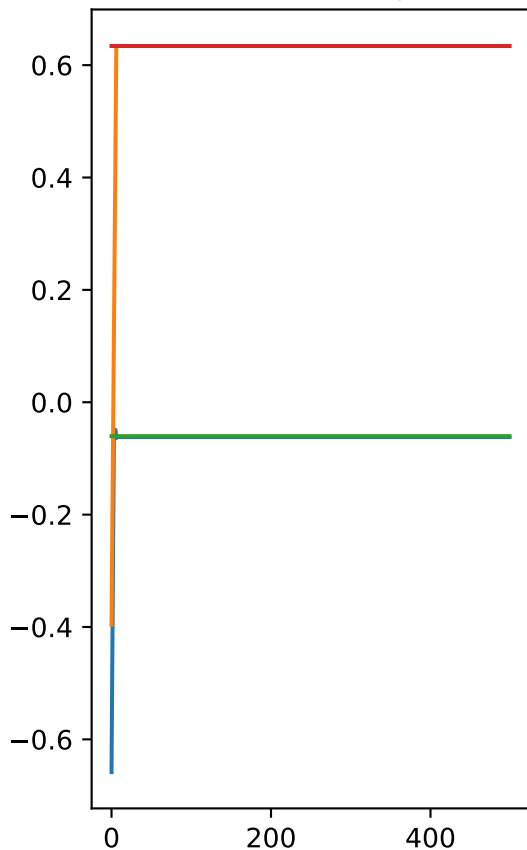
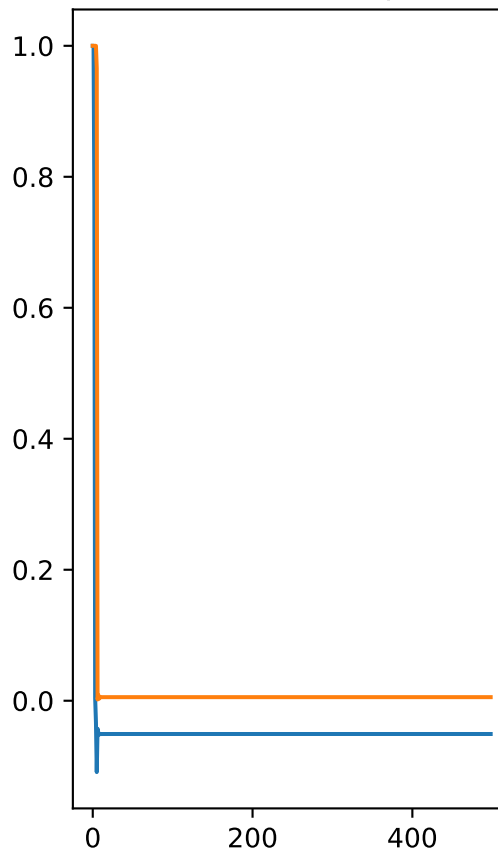


Reward: quartic_root
Speed = 300.83891172878396 [rad/s]

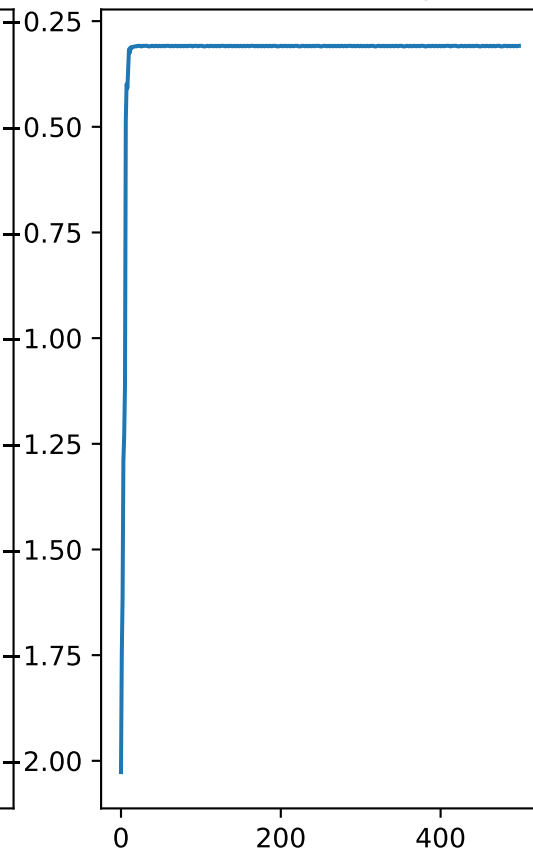
State vs step



Action vs step



Reward vs step



I_d I_{dref}
 I_q I_{qref}

V_d V_q