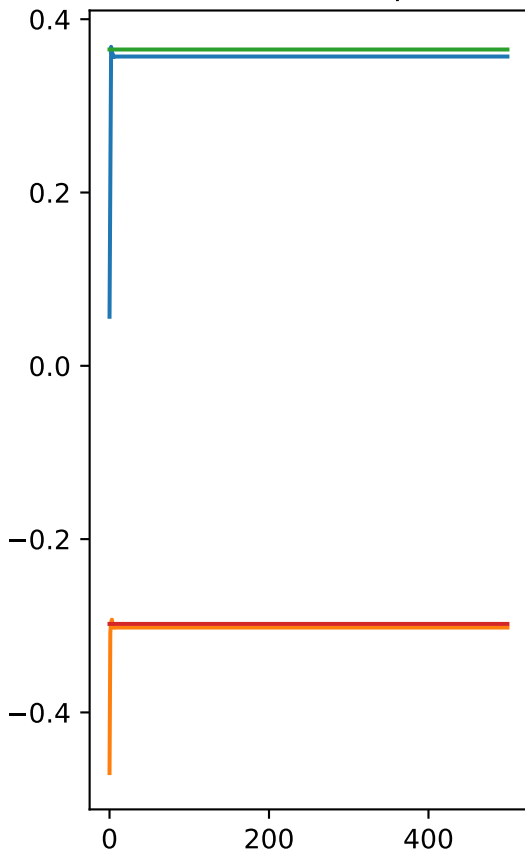
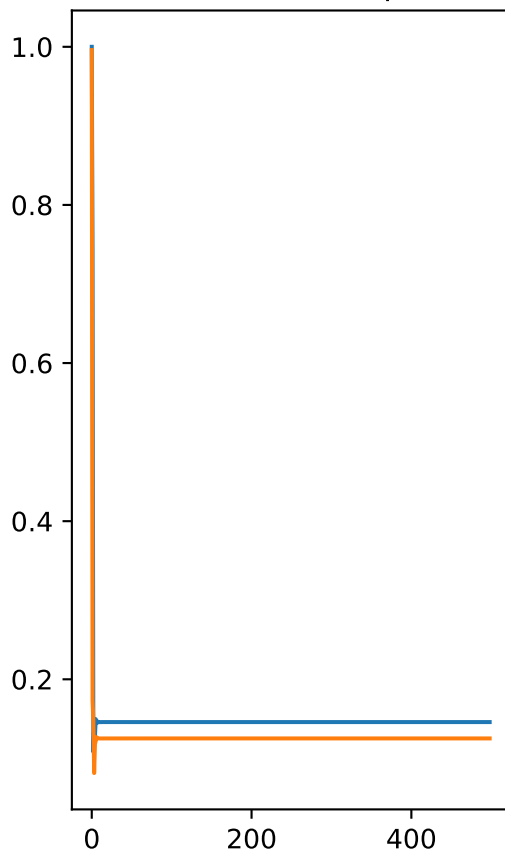


Reward: quartic_root
Speed = 509.05111250211894 [rad/s]

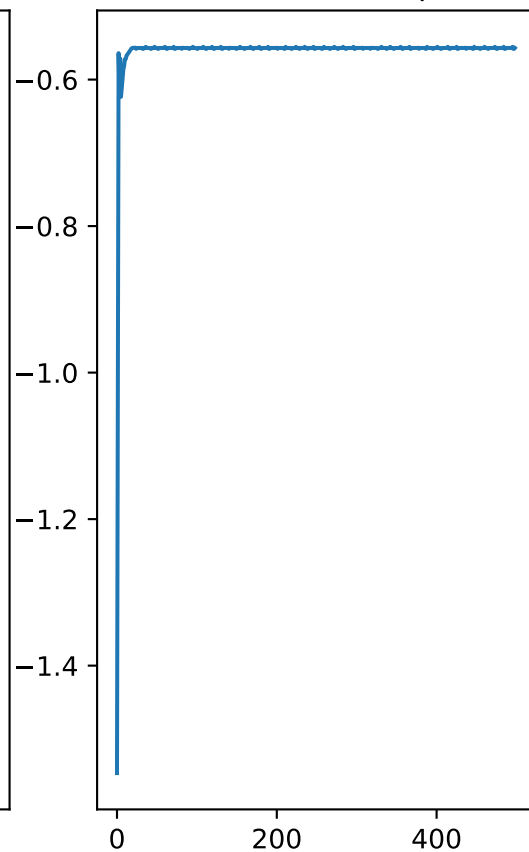
State vs step



Action vs step



Reward vs step



I_d I_{dref}
 I_q I_{qref}

V_d V_q