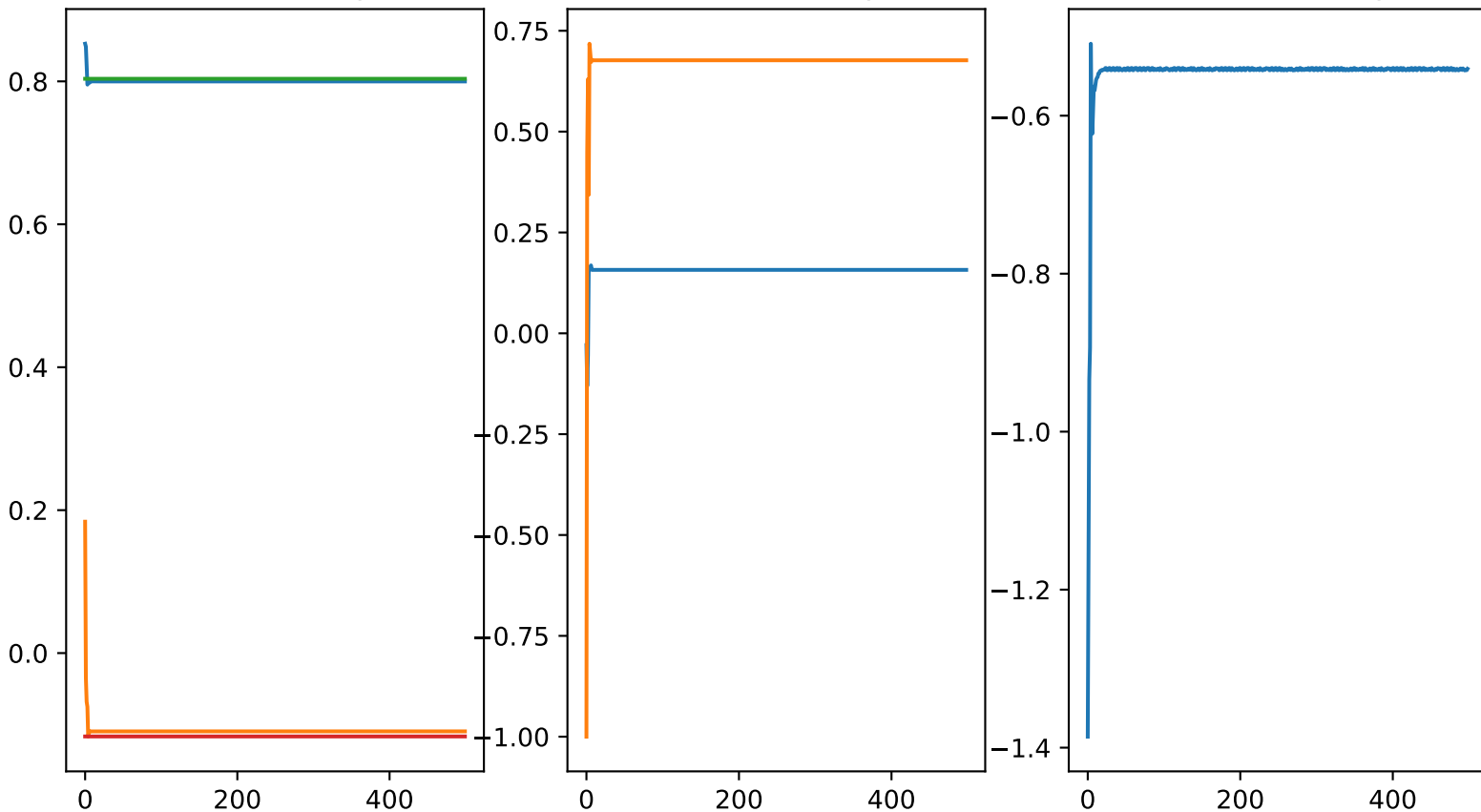


Reward: quartic_root
Speed = 818.5985110611916 [rad/s]

State vs step

Action vs step

Reward vs step



— I_d — I_{dref}
— I_q — I_{qref}

— V_d — V_q