

# Test Report

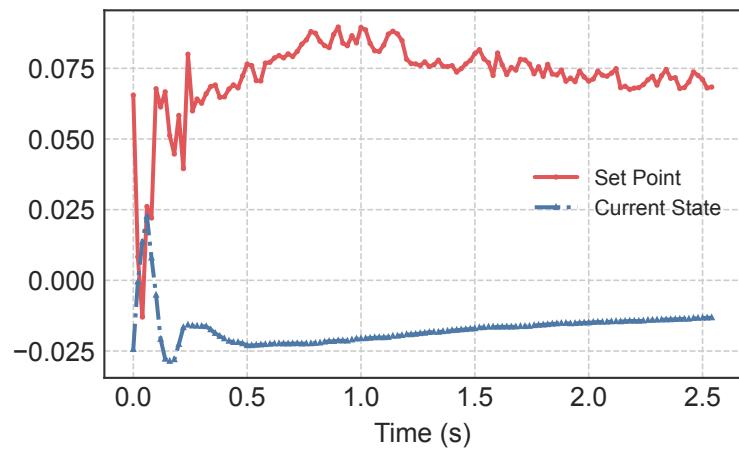
Report generated on: 2025-03-18 14:52:57

This report provides an in-depth overview of key performance metrics, encompassing the following analyses:

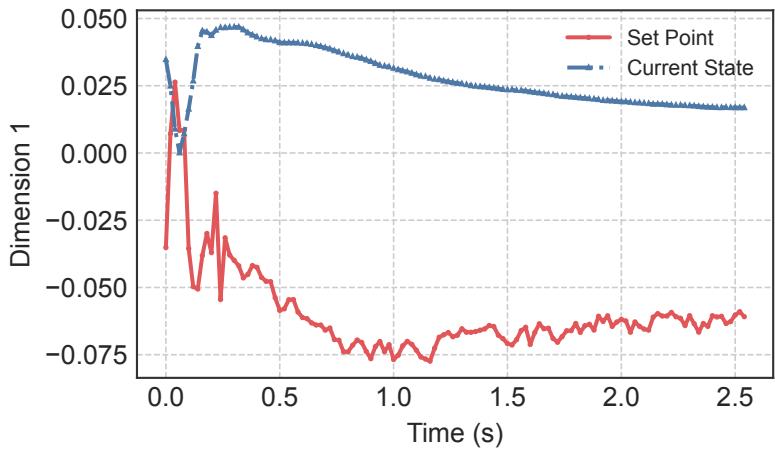
- Set Points vs. Actual State
- Command vs. Actual Values
- Action oscillation
- Actual Torques

# Set Points vs. Actual State

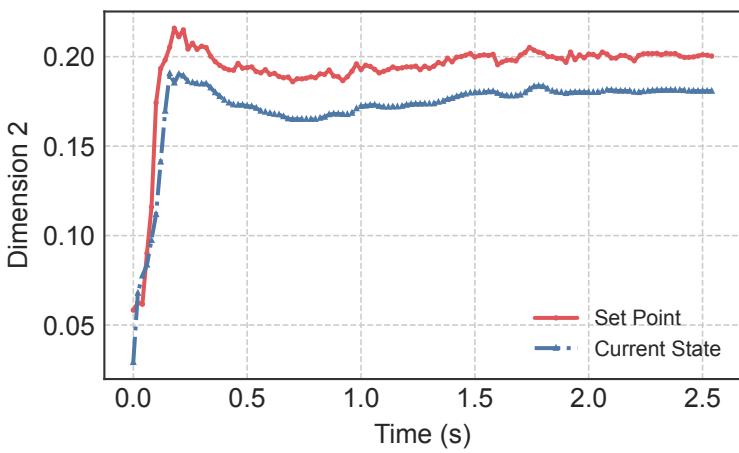
Dimension 0



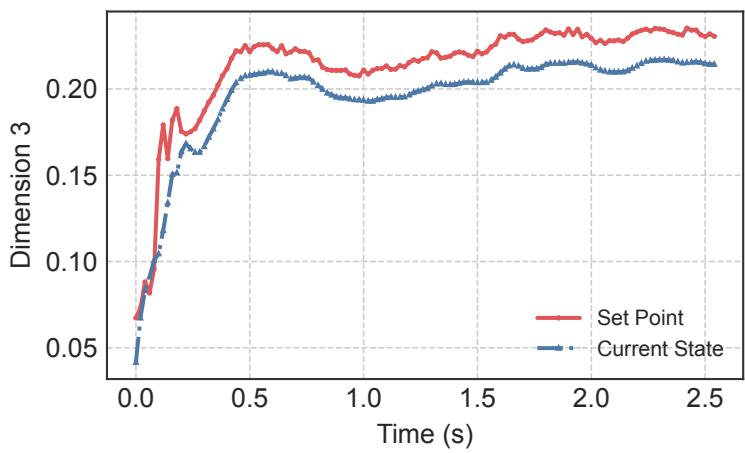
Dimension 1



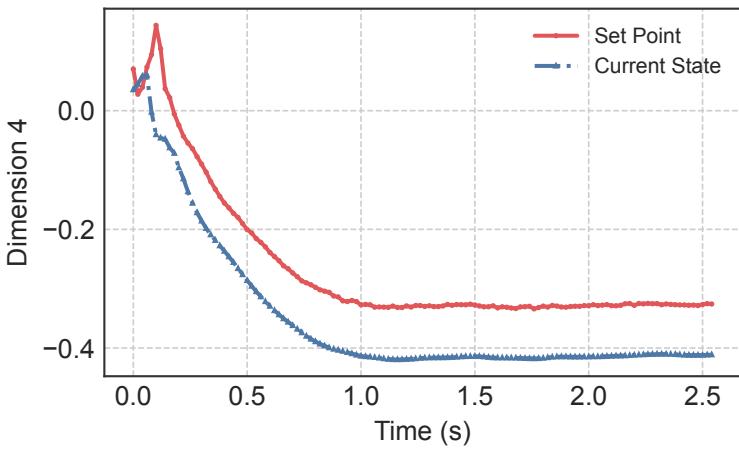
Dimension 2



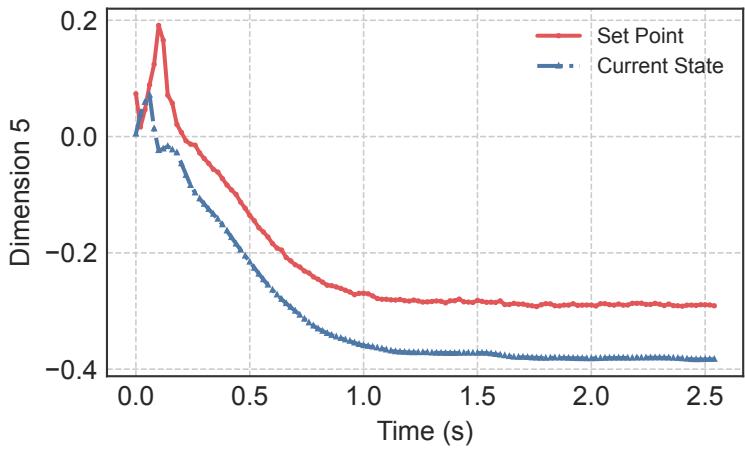
Dimension 3



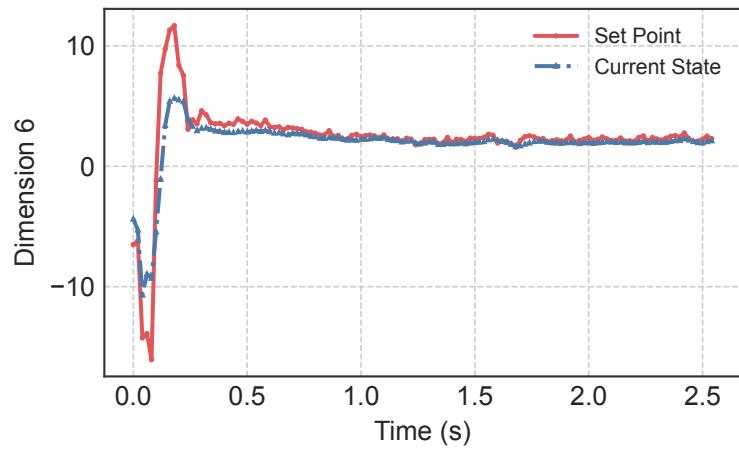
Dimension 4



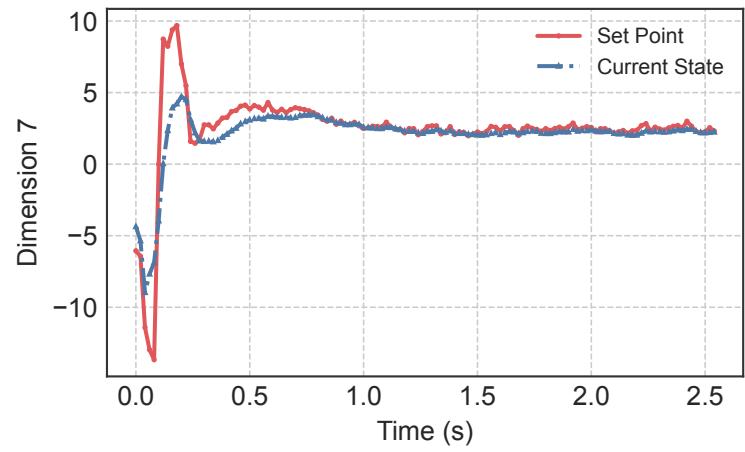
Dimension 5



Dimension 6

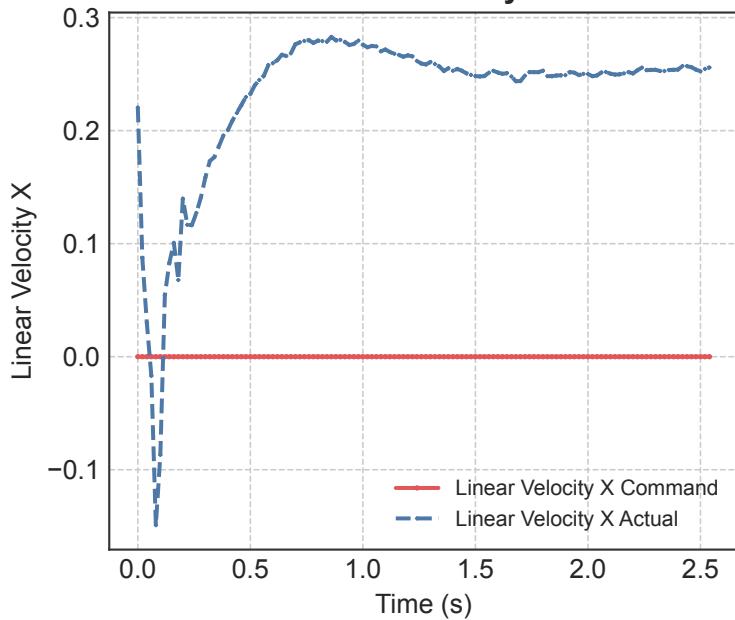


Dimension 7

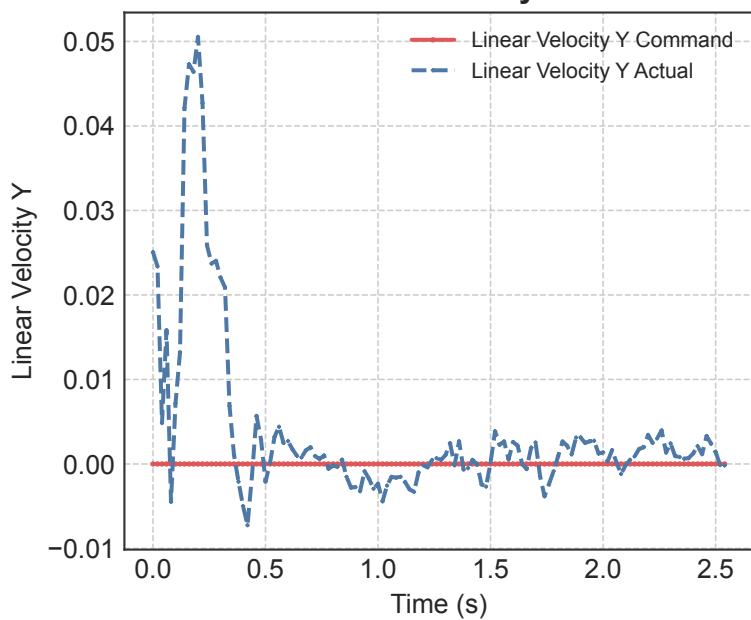


# Command vs. Actual Values

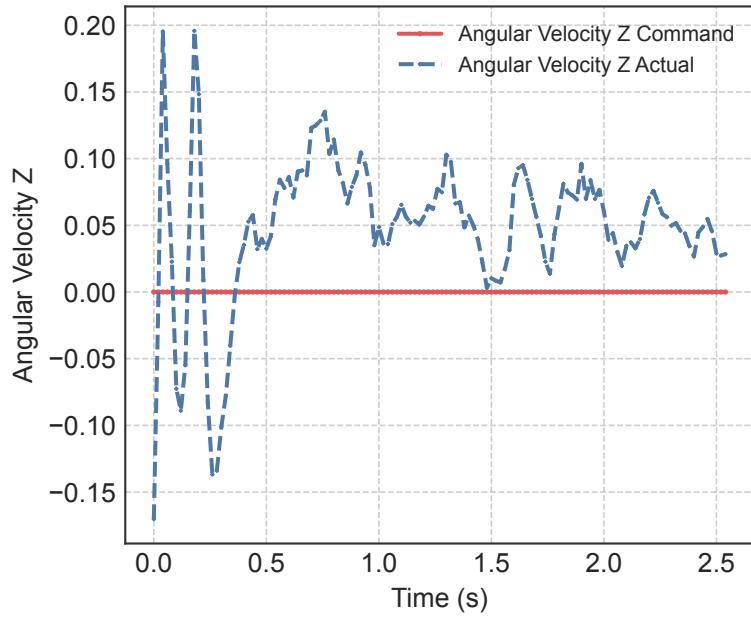
## Linear Velocity X



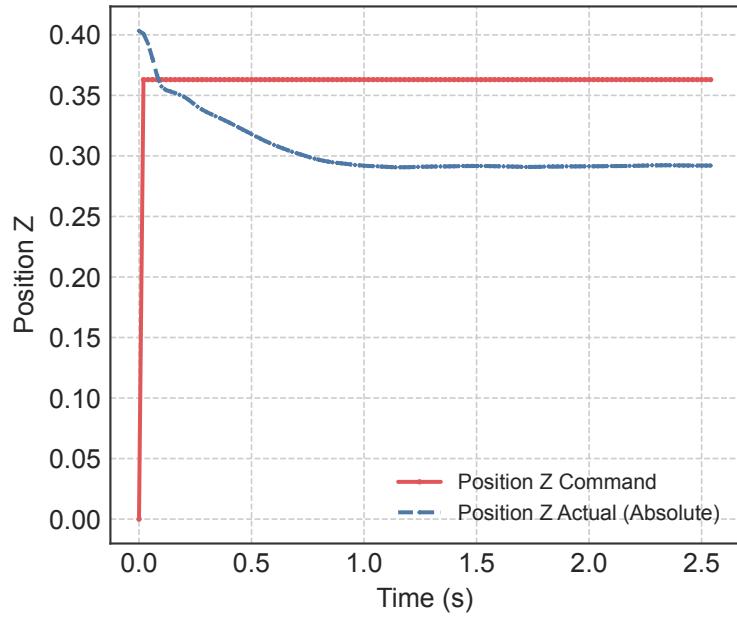
## Linear Velocity Y



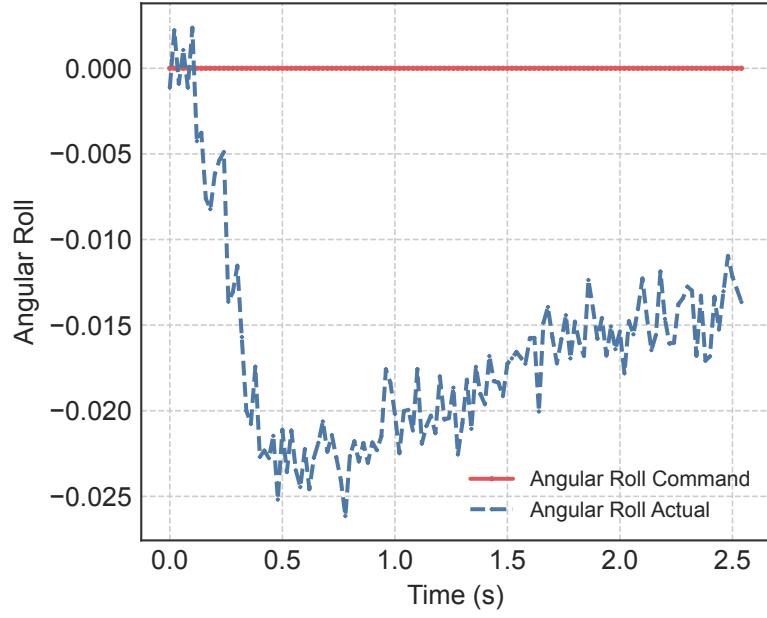
## Angular Velocity Z



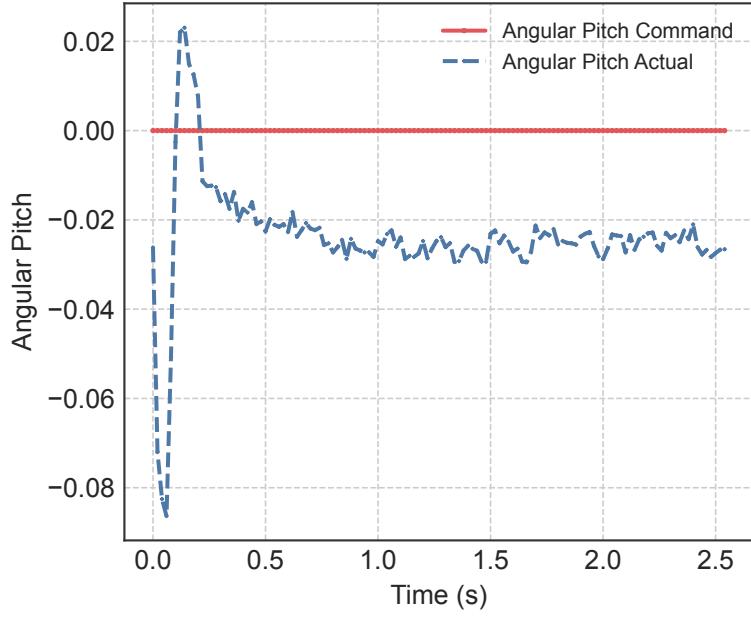
## Position Z



## Angular Roll

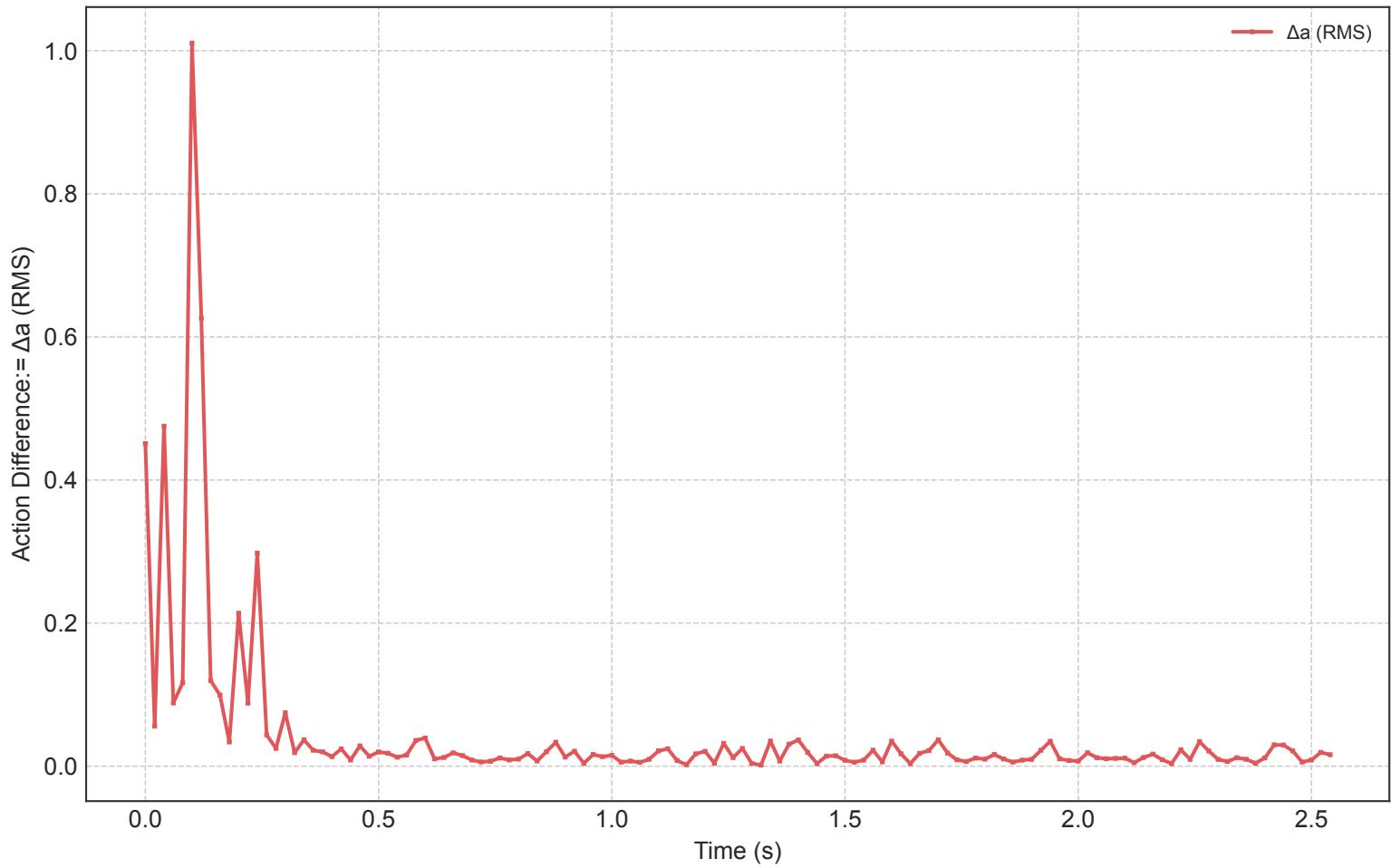


## Angular Pitch

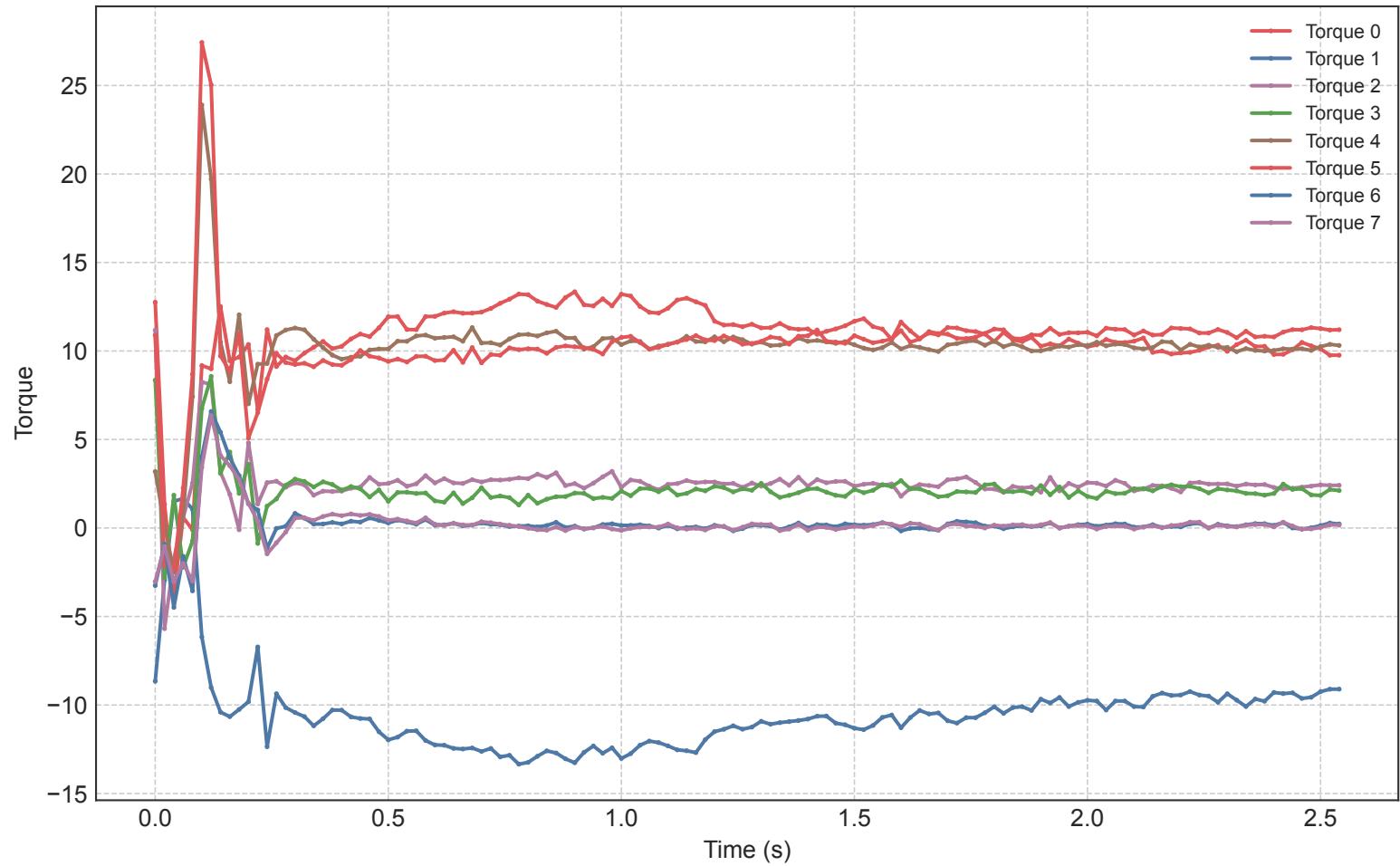


# Action Difference (Oscillation) and Torques

Action Difference (Oscillation)



Torque of Each Joint



# Configuration

Parameter	Value
<b>env</b>	
id	flamingo_v1_4_1
terrain	flat
action_in_state	True
time_in_state	False
max_duration	180.0
observation_dim	20
command_dim	6
action_dim	8
num_stack	3
<b>policy</b>	
use_lstm	False
h_in_dim	256
c_in_dim	256
onnx_file	policy_sample_v1_3.onnx
<b>random</b>	
precision	medium
sensor_noise	low
init_noise	0.05
sliding_friction	0.3
torsional_friction	0.02
rolling_friction	0.01
friction_loss	0.1
action_delay_prob	0.05
mass_noise	0.05
load	0.0
<b>hardware</b>	
Kp_hip	120.0
Kp_shoulder	120.0
Kp_leg	120.0
Kd_hip	2.0
Kd_shoulder	2.0
Kd_leg	2.0
Kp_wheel	0.0
Kd_wheel	0.5
joint_max_torque	45.0
wheel_max_torque	45.0