

# Test Report

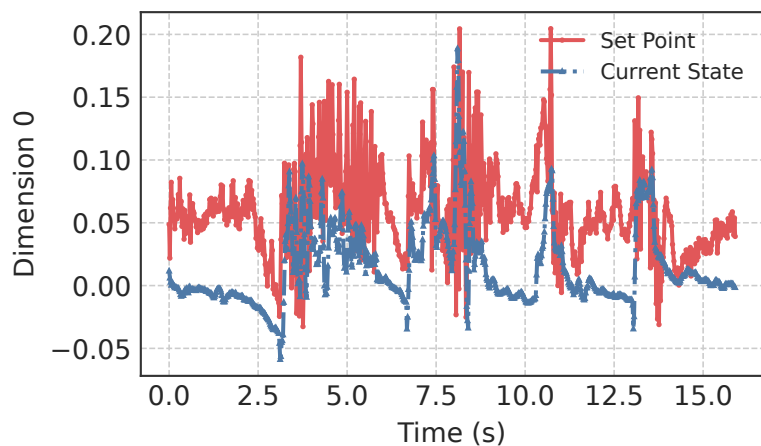
Report generated on: 2025-05-18 17:36:29

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

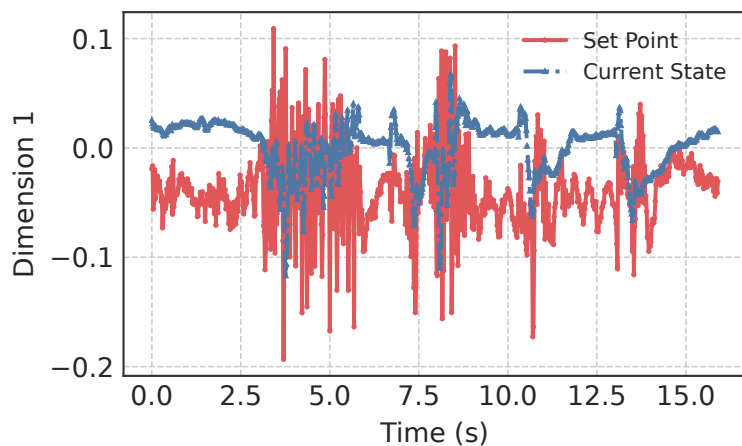
- Set Points vs. Actual State
- Command vs. Actual Values
- Action oscillation
- Actual Torques

# Set Points vs. Actual State

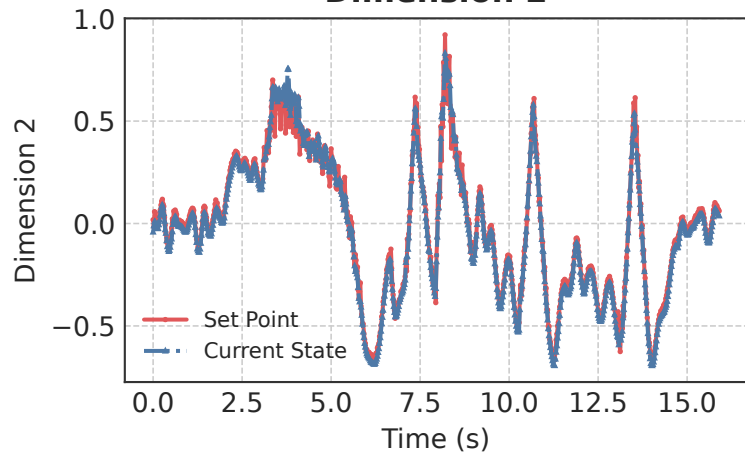
## Dimension 0



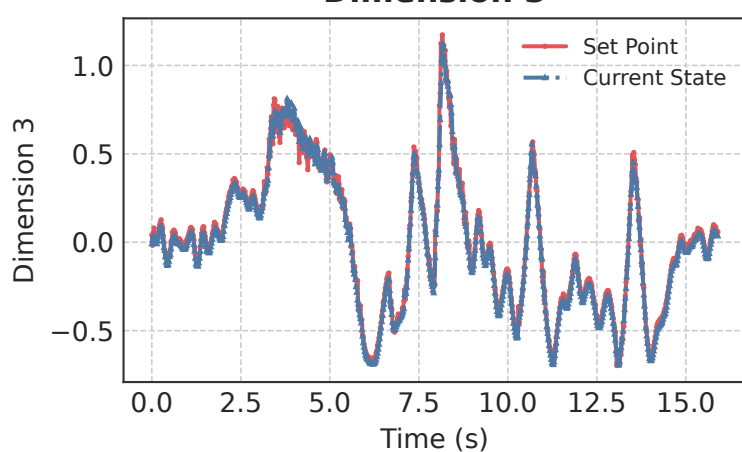
## Dimension 1



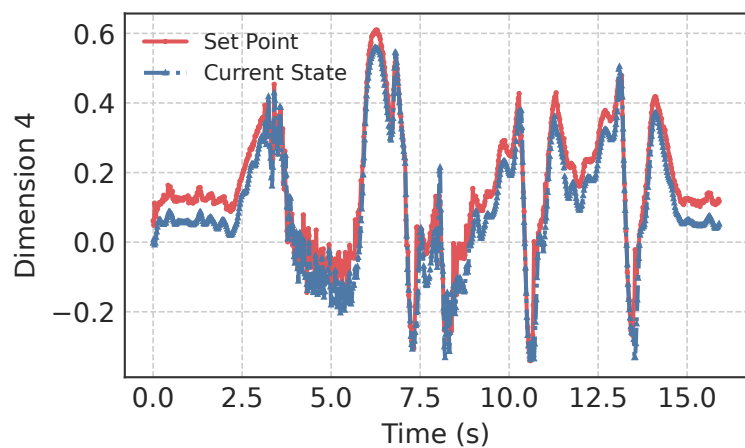
## Dimension 2



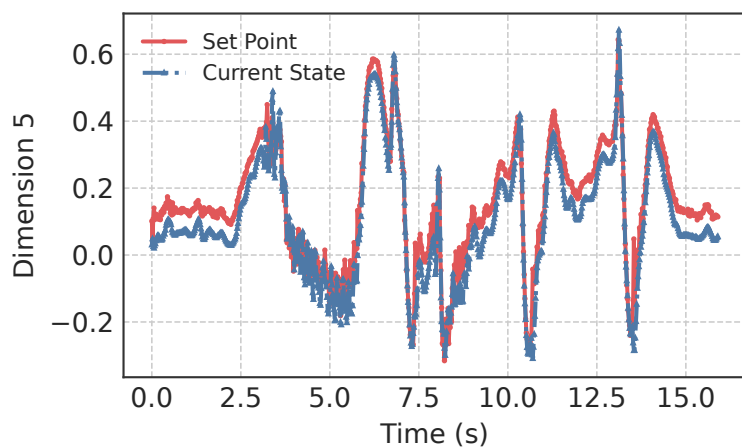
## Dimension 3



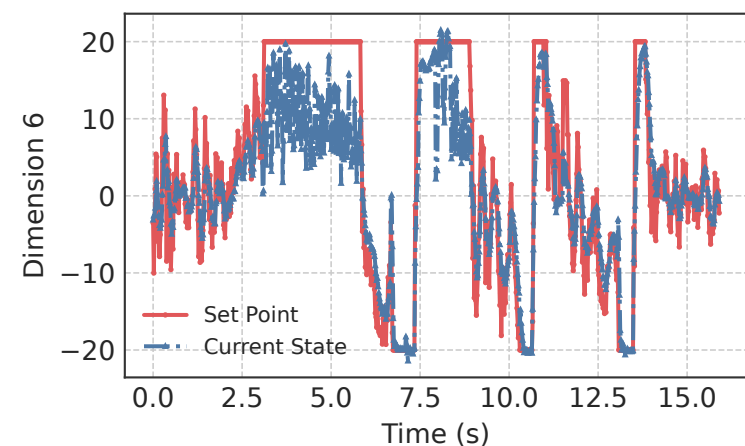
## Dimension 4



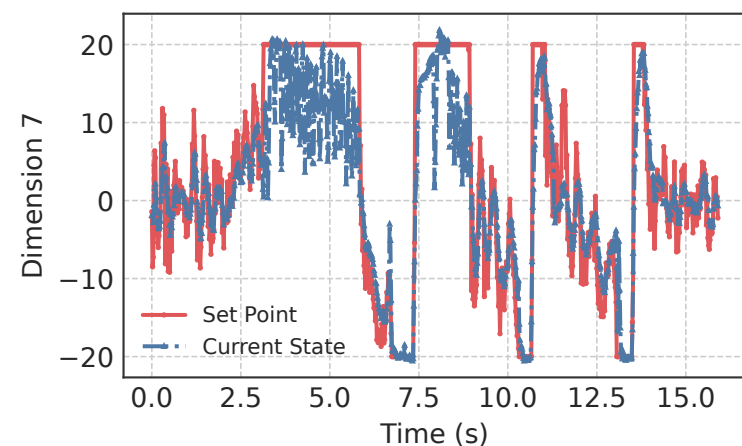
## Dimension 5



## Dimension 6

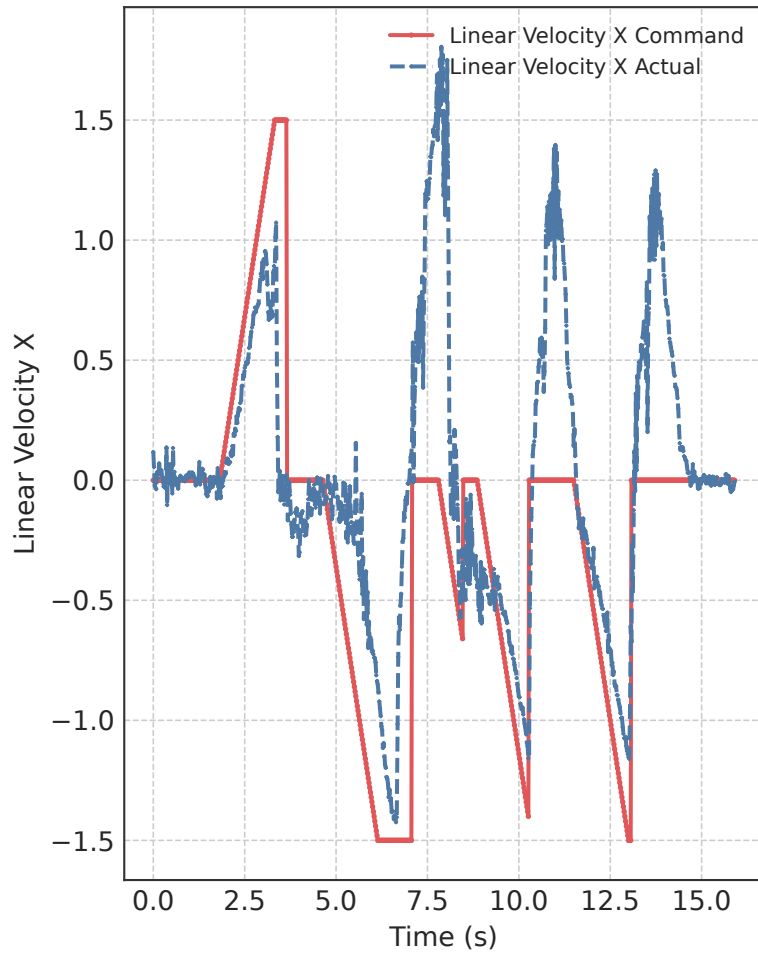


## Dimension 7

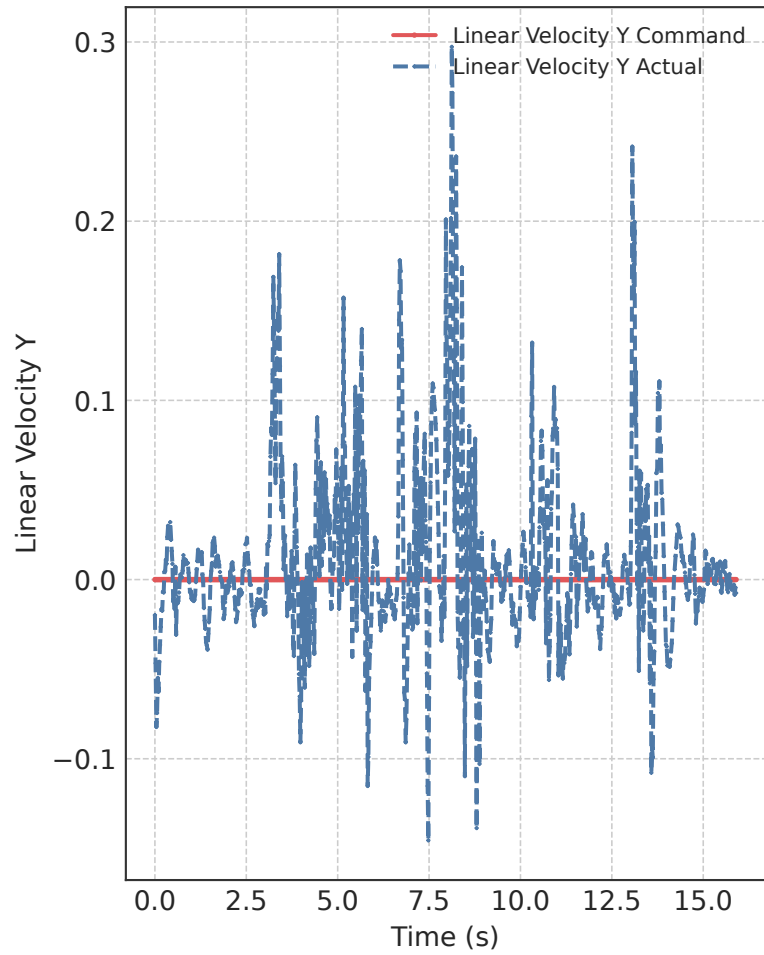


# Command vs. Actual Values

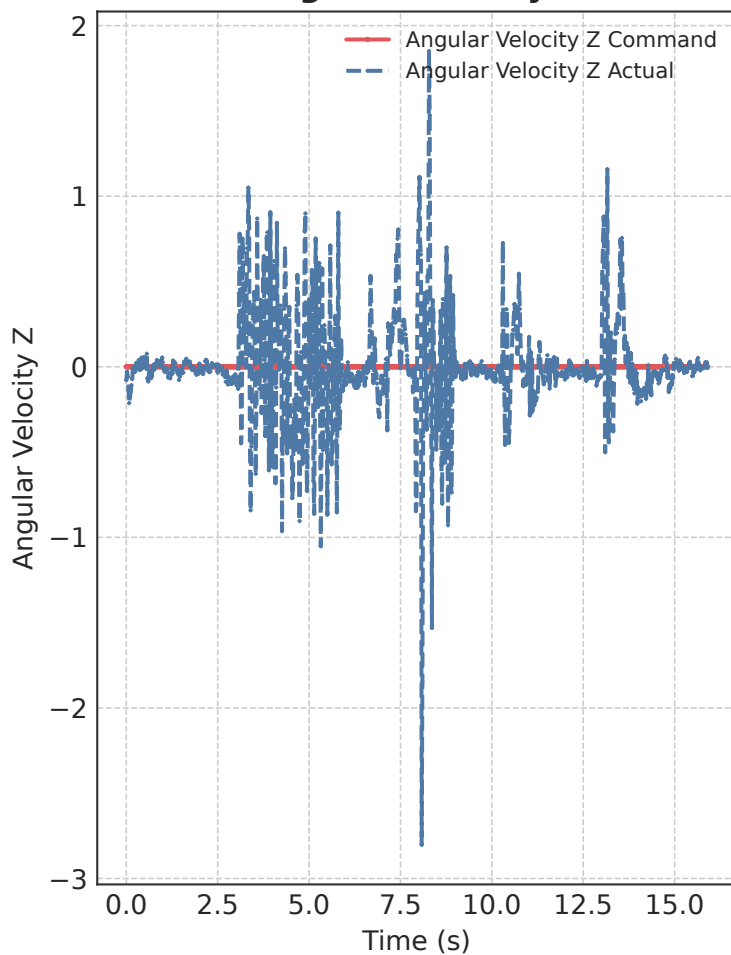
## Linear Velocity X



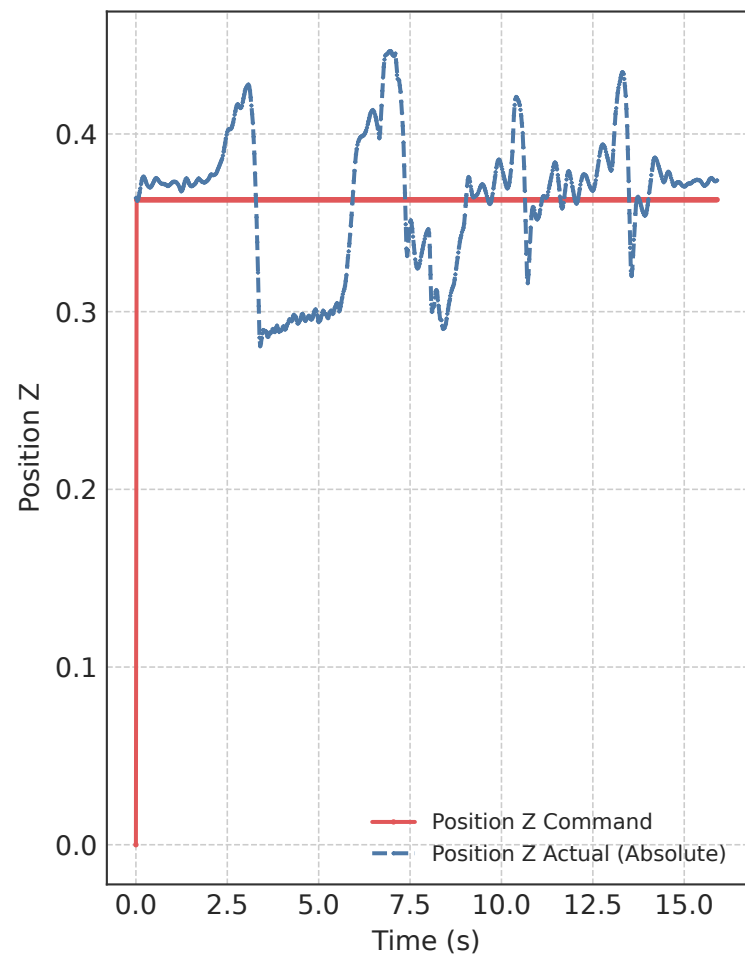
## Linear Velocity Y



## Angular Velocity Z

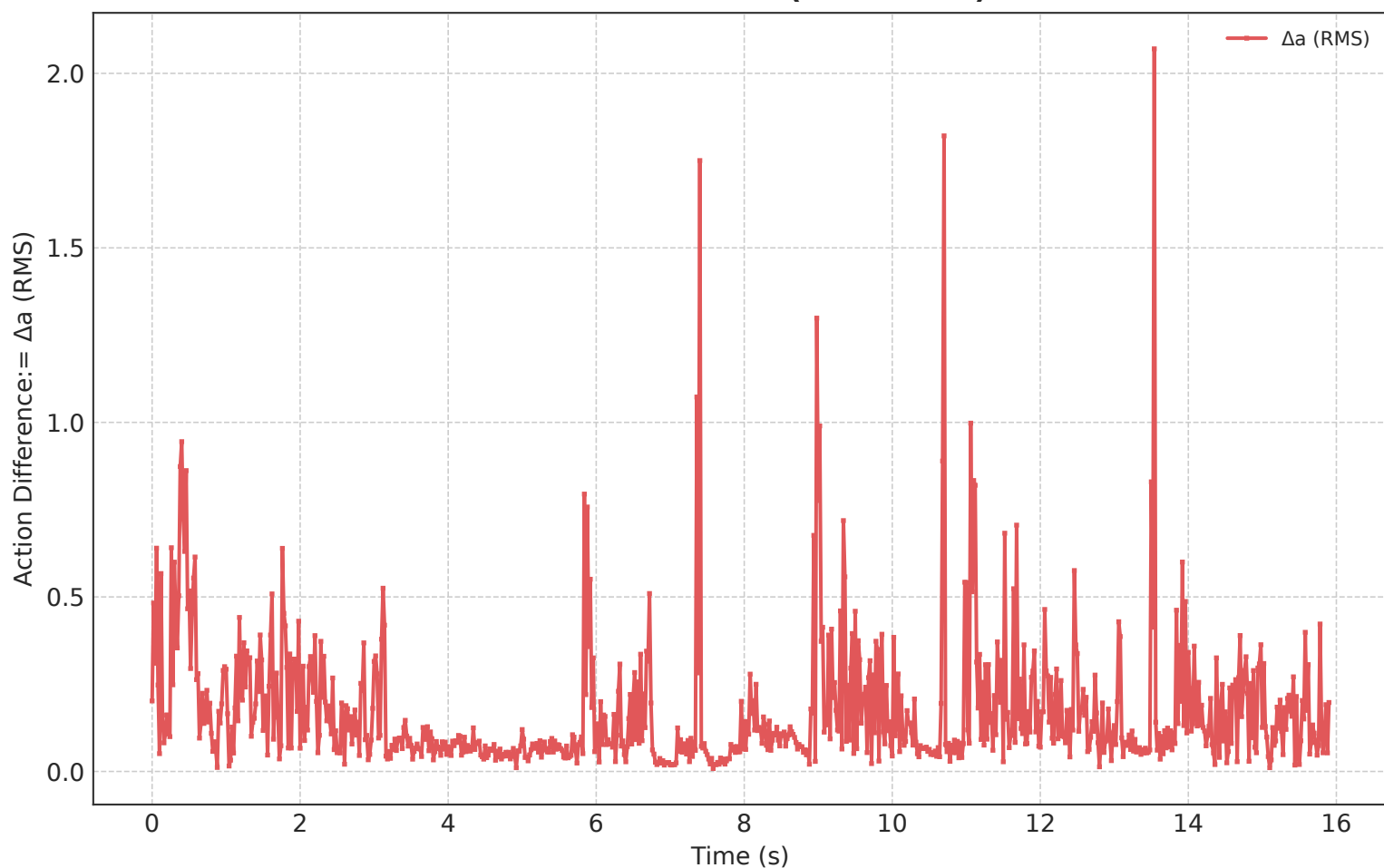


## Position Z

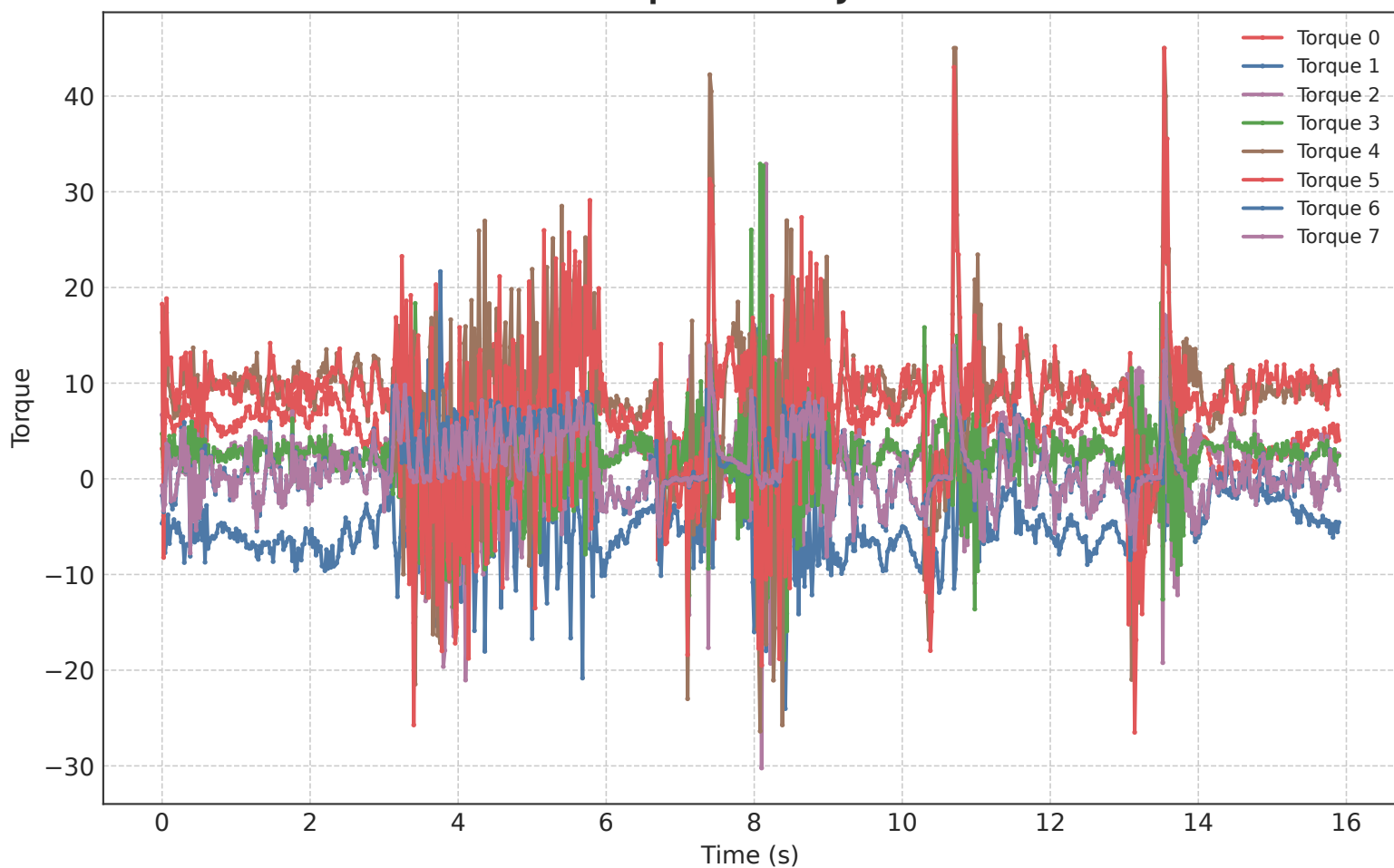


# Action Difference (Oscillation) and Torques

## Action Difference (Oscillation)



## Torque of Each Joint



# Configuration

Parameter	Value
<b>env</b>	
id	flamingo_v1_5_1
terrain	stairs_hard
action_in_state	True
time_in_state	False
max_duration	180.0
observation_dim	20
command_dim	4
action_dim	8
num_stack	3
<b>policy</b>	
use_lstm	False
h_in_dim	256
c_in_dim	256
onnx_file	policy.onnx
<b>obs_scales</b>	
lin_vel	1.0
ang_vel	1.0
dof_pos	1.0
dof_vel	1.0
<b>random</b>	
precision	extreme
sensor_noise	extreme
init_noise	0.05
sliding_friction	0.8
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	100.0
Kp_shoulder	100.0
Kp_leg	150.0
Kd_hip	1.5
Kd_shoulder	1.5
Kd_leg	2.0
Kp_wheel	0.0
Kd_wheel	0.5
joint_max_torque	45.0
wheel_max_torque	45.0