Algorithm 1 Main Loop

```
 1: procedure MAIN
 2:     EPISODES ← 200
 3:     ITERATIONS ← 100
 4:     clientID ← startCommunication()
 5:     jointHandles ← getJointHandles(clientID)
 6:     jointPos ← getJointPositions(clientID,jointHandles)
 7:     cartesianJointPos ← getJointPositions(clientID,jointHandles)
 8:     velStart ← 0
 9:
10:     for i ← 0,  EPISODES do
11:         Start Simulation
12:         for j ← 0,  ITERATIONS do
13:             velEnd ← getNewVelocity(clientID,jointPos)
14:
15:             Save jointPos,cartesianJointPos,velStart,velEnd
16:
17:             velStart ← smoothTrajectory(clientID,jointPos,velStart,velEnd)
18:             jointPos ← getJointPositions(clientID,jointHandles)
19:             cartesianJointPos ← getJointPositions(clientID,jointHandles)
20:
21:         Stop Simulation
```