Function: Rotation-phase()
1. Set *current_state* = START_STATE
2. **while** (*current_state* != FINAL_STATE)
3.   Set action *a* to observed human action
4.   Sample robot action from *T*(*current_state*, *a*, *next_state*)
5.   Record current_state, *a*
6.   *current_state* = *next_state*
7. **end while**