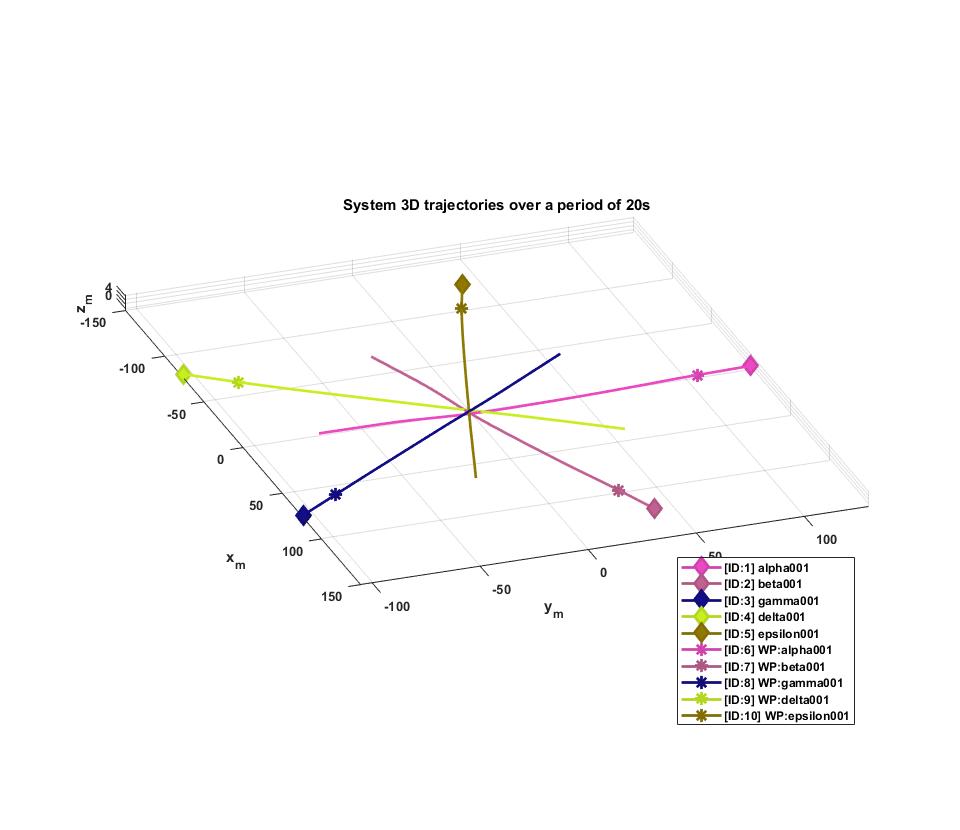
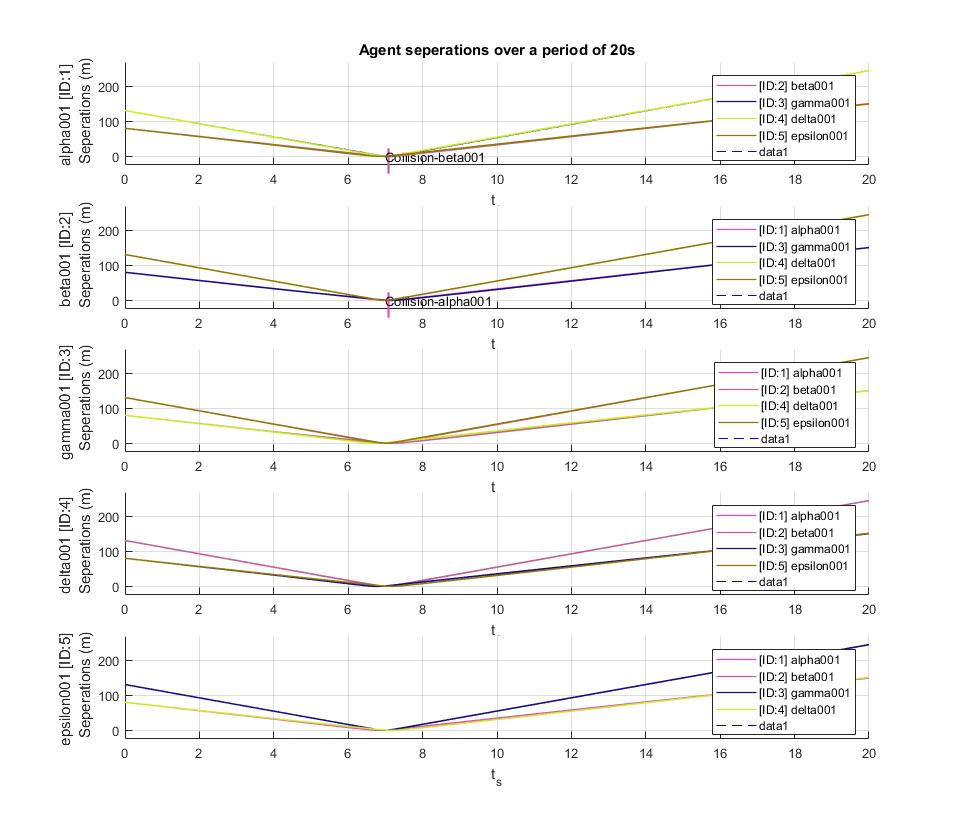
Prelimary results with the velocity obstacle approach



Agent seperations



Agent control inputs

