

Workspace

- robots: std::vector<Robot>
- sim: RVO::RVOSimulator
- robot_goals: std::vector<RVO::vector>

- + perform_iteration():void
- + update_environment(num_robots, current_positions, current_velocities): void
- + getRobotDesiredVelocities(): std::vector<std::vector<double>>
- + getRobotDesiredPositions(): std::vector<std::vector<double>>