Environment

- agents: std::vector<SimAgent> *
- sim: RVO::RVOSimulator *
- agent_goals: std::vector<RVO::vector>
- reached_goals: std::vector<RVO::vector>
- sim_timer: rclcpp::TimerBase::SharedPtr
- goal_radius: double
+ total_sim_time: double

+ Environment(num_agents,goal_positions)
- change_goal_position(agent_number,new_goal_pos):void
- reached_goal(agent_number):bool
+ perform_iteration():void
+ ~Environment()

SimAgent

- vel_pub: rclcpp::Publisher<geometry_msgs::msg::Twist>::SharedPtr
- odom_sub: rclcpp::Subscription<nav_msgs::msg::Odometry>::SharedPtr
- positon: std::vector<double>
- velocity: std::vector<double>

+ SimAgent(initial_pos,intial_vel)
+ move_agent(new_vel)
+ ~SimAgent()