**Given:**

* L1L​: Length of the first link (from the base to the first joint)
* L2L​: Length of the second link (from the first joint to the second joint)
* θ1: Angle of the first link with the horizontal axis
* θ2​: Angle of the second link relative to the first link

**Forward Kinematics Equations:**

1. **Coordinates x and y of the end-effector:**

x=L1​⋅cos(θ1​)+L2​⋅cos(θ1​+θ2​)

y=L1​⋅sin(θ1​)+L2​⋅sin(θ1​+θ2​)

**Explanation of the Equations:**

* X and y are the coordinates of the position where the robotic arm will reach.
* θ1 ​ and θ2 are the angles of each link relative to the horizontal axis.
* L1​ and L2 are the lengths of the connected parts.