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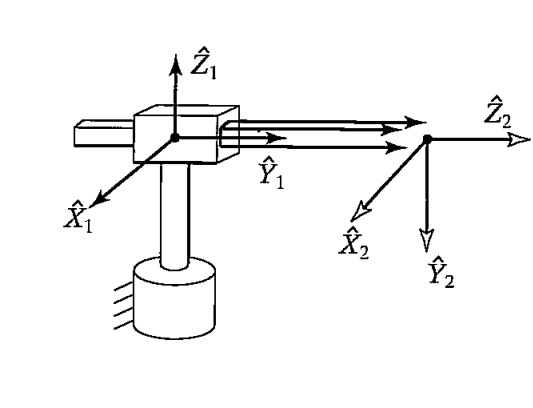
**1.** webots file has been attached.

**2.**

Reachable workspace is a disc of radius (maximum length that robot arm can be extended to). Dextrous workspace is only one point (at the center of Reachable disc).

**3.**

Subspace is a plane with . workspace is a disc which mentioned in the previous part. The subspace considering having relative to the base frame



we need to find for first joint and for the second joint (third joint is more complex and needs the orientation of target).

**4.** Controller and robot files are attached. Explanation is given in the video.