

Robot
<ul style="list-style-type: none"><li>- joint1:Vector2f</li><li>- joint2:Vector2f</li><li>- endEffector:Vector2f</li></ul>
<ul style="list-style-type: none"><li>+ isInWorkspace(double x,double y):bool</li><li>+ targetReached(double x,double y):bool</li><li>+&lt;&lt;constructor&gt;&gt;Robot(Vector2f joint1,Vector2f joint2,Vector2f endEffector)</li></ul>