## **ACTIVITY DIAGRAM**

## **UML DIAGRAM**

## Inverse\_kinematics

- length[]: double +angle[]: double

-x\_initial: double

-y\_initial: double -z\_initial: double

+x\_final: double

+y\_final: double

+z\_final: double

+ input\_end\_point(double x, double y, double z):

+ ik\_solve(double phi): void

+ set\_initial(): void

+limit\_movement():void

