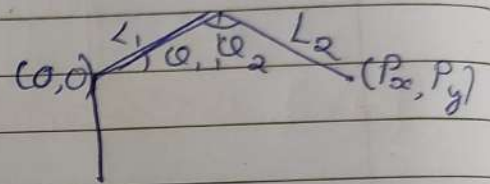


Position of end effector = $\vec{L}_1 + \vec{L}_2$



$$P_x = L_1 \cos \theta \rightarrow L_2 \cos (\pi - (\theta_1 + \theta_2))$$
$$= L_1 \cos \theta - L_2 \cos (\theta_1 + \theta_2)$$

$$P_y = L_1 \sin \theta \mp L_2 \sin (\pi - (\theta_1 + \theta_2))$$
$$= L_1 \sin \theta \mp L_2 \sin (\theta_1 + \theta_2)$$

For the robotic arm, $L_1 = 25\text{cm}$ and $L_2 = 30\text{cm}$