1. Assign coordinate frames to each link according to the Denavit-Hartenberg convention and the following rules:
   a) The base frame (frame 0) should be as indicated in the figure. Its origin should coincide with the co-intersection point of axes 0, 1, 2, and 5.
   b) The end-effector frame should be as shown in the figure.
   c) To the maximum extent possible, make $r_i$ and $d_i$ be equal to zero.

2. Identify the kinematic parameters of the robot by filling in the D-H table below.

3. If at the configuration shown in the figure, axis 1 has a joint motion range of $\pm 115^\circ$, determine the joint motion range in terms of $q_2$ (joint variable for 2nd joint, assigned according to the Denavit-Hartenberg convention, item 1 above.).