— To treat the first part (QI and QII), the DH-parameters table corresponding to figure 1 is not the same that presented on the slides of M. Martinet. The correct table corresponding to the configuration robot drawing on figure 1 is :

j	a(j)	α_j	d_j	θ_j	r_j
1	0	0	0	θ_1	0
2	1	$\pi/2$	0	θ_2	0
3	2	0	$D3$	θ_3	0
4	3	$-\pi/2$	0	θ_4	$RL4$
5	4	$\pi/2$	0	θ_5	0
6	5	$-\pi/2$	0	θ_6	0

— For Q-III, follow the theory presented in section 2.5, pages 32 and 33 (attached). In addition, I give you the DGMRX matlab file (elaborated by using Symoro+, a Software used to elaborate all symbolic models) used to compute the DGM of any robot.

— Finally, for the Q-IV, attached you can find the DGM2R (DGM for 2R planar Robot).