l_1 l_2 l_3

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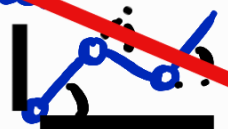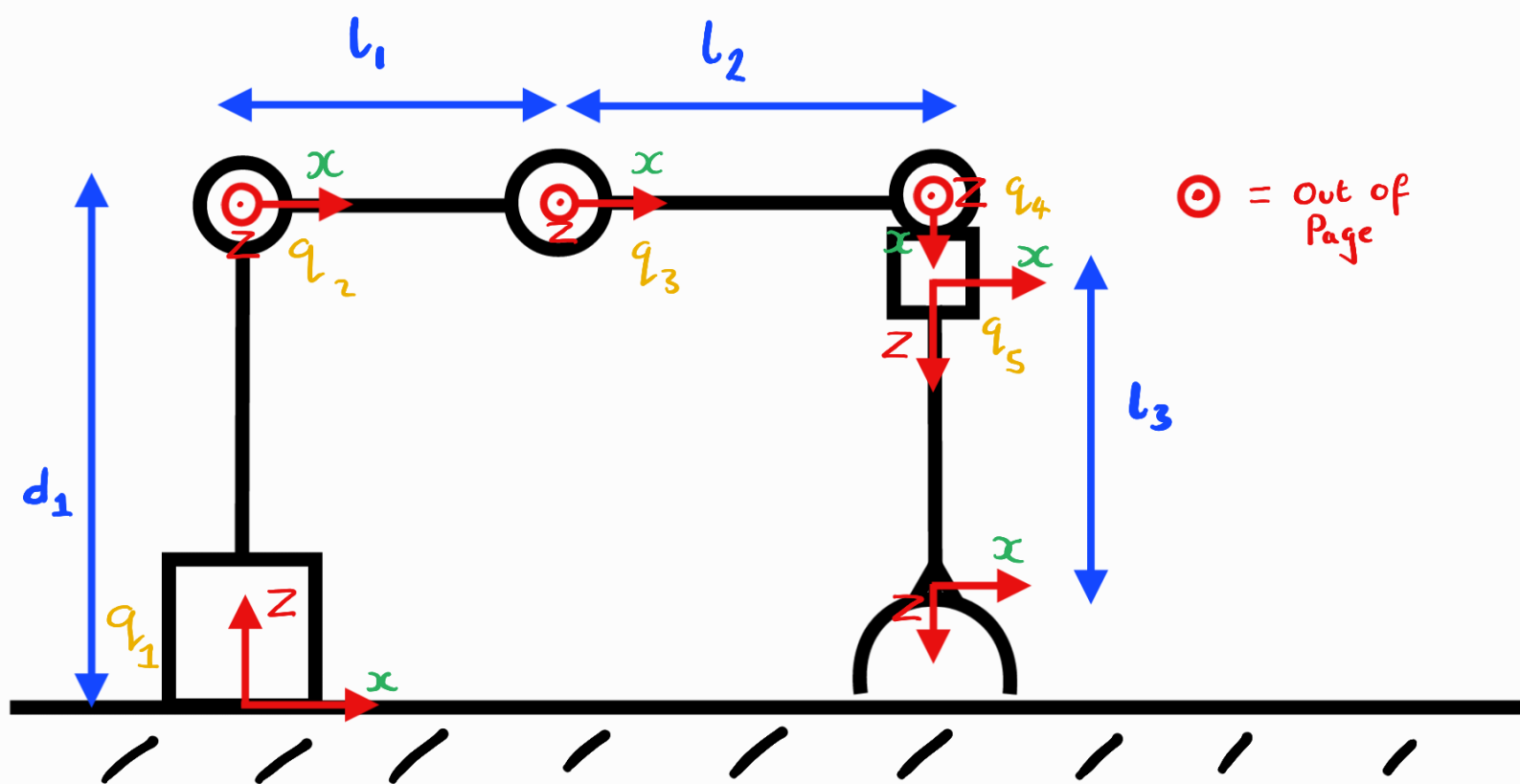z q_2 x z q_3 x z q_4 x x q_5 z x z

d_1

z q_1 x

~~Dist between j4 and j5 actually zero but regarding l_3 as this distance, rather than q to end effector distance, makes calcs way easier. → lets you regard mid 3 as planar robot:~~

l_5

Distal DH table:

n	a	α	d	θ

1	0	90	d_1	q_1
2	l_1	0	0	q_2
3	l_2	0	0	q_3
4	0	90	0	q_4
5	0	0	l_3	q_5

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$$
\left[
\begin{array}{ccc|c}
 & & & \\
 & 3 \times 3 & & 1 \times 3 \\
 & \text{Rotation} & & \text{translation Vector} \\
 & \text{Matrix} & & \\
\hline
0 & 0 & 0 & 1
\end{array}
\right]
$$