```
function [Cost] =  fnCostComputation(x_traj,u_new,p_target,dt,Q_f,R,Q)


 [numOfStates,Horizon] = size(x_traj);
 Cost = 0;

 for j =1:(Horizon-1)

    Cost = Cost + (0.5 * u_new(:,j)' * R * u_new(:,j) * dt)+ (0.5 *
 x_traj(:,j)' * Q * x_traj(:,j) * dt);

 end

 TerminalCost= (x_traj(:,Horizon) - p_target)'*Q_f * (x_traj(:,Horizon) -
 p_target);

 Cost = Cost + TerminalCost;
end
```

```
Not enough input arguments.

Error in fnCostComputation (line 4)
 [numOfStates,Horizon] = size(x_traj);
```

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