```
function newCoords = rotate(oldCoords, yaw, pitch, roll)
    % Yaw rotates about z axis
    % Pitch rotates about y axis,
    % Roll rotates about x axis
    % Angles taken in degrees

    pitch = pi*(pitch/180);
    yaw = pi*(yaw/180);
    roll = pi*(roll/180);

    rotateMatrix = [
                     cos(yaw)*cos(pitch), cos(yaw)*sin(pitch)*sin(roll)
 - sin(yaw)*cos(roll), cos(yaw)*sin(pitch)*cos(roll) +
 sin(yaw)*sin(roll);
                     sin(yaw)*cos(pitch), sin(yaw)*sin(pitch)*sin(roll)
 + cos(yaw)*cos(roll), sin(yaw)*sin(pitch)*cos(roll) -
 cos(yaw)*sin(roll);
                     -sin(pitch)        , cos(pitch)*sin(roll)
                      , cos(pitch)*cos(roll)
                    ];

    newCoords = rotateMatrix*oldCoords;
end
```

```
Not enough input arguments.

Error in rotate (line 7)
    pitch = pi*(pitch/180);
```

Published with MATLAB® R2021a