
```
% Rotational Kinematics
function eul_dot = euler_kinematics(phi, theta, psi, pqr)
p = pqr(1);
q = pqr(2);
r = pqr(3);

cphi = cos(phi);
sphi = sin(phi);
cth = cos(theta);
sth = sin(theta);

T = [ 1, sphi*sth/cth, cphi*sth/cth;    % = [1, sin(phi)*tan(theta),
cos(phi)*tan(theta)]
      0, cphi, -sphi;
      0, sphi/cth, cphi/cth];

eul_dot = T * [p; q; r];

end

Not enough input arguments.

Error in euler_kinematics (line 3)
p = pqr(1);
^~~~~~
```

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