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```
function [ dx ] = odethetatracking( t,X)
```

Implementation

```
        %Controller equation
        theta=10;
        theta_cap =X(1);
        x=X(2);
        theta_cap_dot=x*x;
        x_dot= theta*x -(theta_cap+1)*x;
```

```
Not enough input arguments.

Error in odethetatracking (line 6)
        theta_cap =X(1);
```

Calculate x_dot and estimate of the dynamics of the robot

```
       dx=[theta_cap_dot;x_dot];
```

```
end
```

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