

```

function J_tot = inertia(n, n_b, n_n)
    J_m = 5*10^(-7); % kgm^2

    h_r = 0.5 * 0.0254; % m
    m_hub = 65 / 1000; % kg
    J_hub = 1/2 * m_hub * h_r^2; % kgm^2

    f_r = 4.5/2 * 0.0254; % m
    f_t = 0.00468; % m
    f_d = 1.18 / 1000 * 100^3; % kg/m^3
    f_2r = 2 * 0.0254; % m
    f_1r = 1 * 0.0254; % m
    b_r = 0.25 * 0.0254; % m
    J_fw = (pi * f_t * f_d) * ((1/2 * (f_r)^4) - b_r^2*(4*f_1r^2+8*f_2r^2)); % kgm^2

    n_n = n_n * n_b;
    m_b = 7.0874 / 1000; % kg
    m_n = 3.0249 / 1000; % kg
    J_w = (n_b*m_b + n_n*m_n) * (1/2*b_r^2 + 1/2*f_2r^2);

    J_tot = (J_hub + J_fw + J_w) / n^2 + J_m; % kgm^2
end

```

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Not enough input arguments.
Error in inertia (line 16)
    n_n = n_n * n_b;

```

