```
function H = H(Theta)

% Create a H_inverse 3*3 matrix by unpacking theta
phi = Theta(1);
theta = Theta(2);
psi = Theta(3);

H = [1 tan(theta)*sin(phi) tan(theta)*cos(phi);
     0 cos(phi) -sin(phi);
     0 sin(phi)/cos(theta) cos(phi)/cos(theta)];
```

Sample Times for 'rotationalkinematicseuler'

Color	Annotation	Description	Value
■	Cont	Continuous	0
■	Inf	Constant	Inf