

```
% Compute the body velocity twist V of the tool frame or an end-effector for a given manipulator
function Vb = BodyVelTwist(Jb,thetadot)
% compute body velocity twist.
Vb = Jb*thetadot;
end
```

Not enough input arguments.

Error in BodyVelTwist (line 4)  
Vb = Jb\*thetadot;

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