

```
% Compute the spatial velocity twist V of the tool frame or an end-effector for a given manipulator
function Vs = SpatialVelTwist(Js,thetadot)
% compute V. V=J(theta)*thetadot.
Vs = Js*thetadot;
end
```

Not enough input arguments.

Error in SpatialVelTwist (line 4)

Vs = Js*thetadot;

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