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```
%===== hw1b
%=====
%
% function xdot = f(t, x)
%
%
% Performs integration of the dynamics associated to Homework 1,
% Problem b. It needs your help to get coded.
%
% If Matlab complains about column versus row vector then transpose
% the
% result, xdot, before returning.
%
%===== hw1b
%=====
function xdot = f(t, x)

u = 0.2*sin(t);
v = 0.2;

xdot = zeros(3,1); % Force to be a 3x1 (column) vector.
xdot(1) = cos(t) * u; % Add in differential equations.
xdot(2) = sin(t) * u;
xdot(3) = v;

end

Not enough input arguments.

Error in hw1b (line 15)
u = 0.2*sin(t);
```

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