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```
%===== hw1a
%
% function xdot = f(t, x)
%
% Performs integration of the dynamics associated to Homework 1.
% It needs your help to incorporate the input signal.
%
%===== hw1a
%=====
function xdot = f(t, x)

u = sin(t);

xdot = -2.5*x + 0.75*u;

end

Not enough input arguments.

Error in hw1a (line 12)
u = sin(t);
```

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