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```
function zdot2 = f(t, z)

theta = z(3);
xdot2 = 1*cos(theta) - (-1)*sin(theta);
ydot2 = 1*sin(theta) + (-1)*cos(theta);
thetadot2 = 1*0;

zdot2 = [xdot2; ydot2; thetadot2];

end
```

*Not enough input arguments.*

*Error in HW5prob5b (line 3)*  
*theta = z(3);*

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