
```
function state_dot = PendulumDynamics(state, parameters)

    q = state(1:3);
    q_dot = state(4:6);
    F = -10*q(1) - q_dot(1);
    [W, RHS] = PendulumODEMatrices(state, F, parameters);

    state_dot = [q_dot; W\RHS];

end
```

Not enough input arguments.

Error in PendulumDynamics (line 3)
 q = state(1:3);

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