Script for 2011 ME227 HW 2 Problem 1

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(1.3) Experimental vs. bike vs. four wheel model yaw rate & side slip (vary Ux)

No, it seems like the two wheel assumptions of the bicycle model don't introduce much more error than the full nonlinear four wheel model. During sharp turns, there is some deviation, but both the four wheel and the bike model deviate from the experimental data moreso than they deviate from each other.

```
Attempted to access state(3); index out of bounds because numel(state)=2.

Error in ==> slips at 44
          Uy = state(1); Ux = state(3); r = state(2);

Error in ==> hw2_prob1 at 92
    alpha = slips(simulation, vehicle, x(i,:), delta);
```

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