bwd()

Move the GoPiGo back with PID.

Both the motors are turned on and the PID algoritm on the Atmega328 tunes the motors using the encoder readings to make it move back. This is processor intensive for the Atmega chip but helps the GoPiGo to move back in a straight line.

Syntax

```
bwd()
```

Parameter:

None

Return:

1 on success

-1 on error

Example

```
from gopigo import *
bwd()
```