fwd()

Move the GoPiGo forward 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 forward. This is processor intensive for the Atmega chip but helps the GoPiGo to move forward in a straight line.

Syntax

```
fwd()
```

Parameter:

None

Return:

1 on success

-1 on error

Example

```
from gopigo import *
fwd()
```