

```
1  void stasis(){
2      if(motor_on == 0 && (ticksLR == 0 || ticksRR == 0)){
3          telem.println("I am possibly stuck - heheheh !");
4          stasis_err = stasis_err + 1;
5      }
6      if(stasis_err > 5)  stasis_flag = 1;
7  }
8
9  void stasis_correction(){
10     mStop();
11     set_speed(backup_low);
12     mBackward();
13     smartDelay(250);
14     mStop();
15     stasis_err = 0;
16     stasis_flag = 0;
17
18     if( random(10) > 4){
19         mRight();
20         smartDelay(right_45);
21         mStop();
22     } else {
23         mLeft();
24         smartDelay(left_45);
25         mStop();
26     }
27
28 }
29
30
```