Procedure for Collecting Map Generation Training Data

**Objective**: The goal is to continuously capture video of targets and tarp from an altitude of approximately 200 ft while manually modifying the yaw of the UAV through moving over a stitching path and adjusting the roll. We are targeting at least 20-30 images, and ideally multiple passes to determine if images from one pass can be stitched to images of another.

Procedure:

1. Implement code in python that enables the camera to continuously capture video for an indefinite (or very large) period of time and break the images down into frames at a particular rate, while storing roll values at the same rate.
2. Automate the python script in a bash script.
3. Load the code on the Pi
4. Establish connection between Pi and Pixhawk and verify that roll values can be pulled
5. Define arbitrary path/waypoints for moving the plane through to capture footage and set aside targets and tarps along these waypoints
6. Make between 3-4 passes through this path while ensuring the plane has no pitch and by modifying the roll incrementally.