```
# Install OpenCV if needed
 !pip install opencv-python-headless
 from google.colab.patches import cv2_imshow
 # Import required libraries
Show command palette (Ctrl+Shift+P)
 import numpy as np
 import matplotlib.pyplot as plt
 # Load drone video (you can upload your own or use sample)
 from google.colab import files
 uploaded = files.upload() # Upload a video file (e.g., drone.mp4)
 video path = next(iter(uploaded))
 cap = cv2.VideoCapture(video_path)
 # Initialize ORB and FAST
 orb = cv2.ORB_create()
 fast = cv2.FastFeatureDetector_create()
 # Read first frame
 ret, prev_frame = cap.read()
 if not ret:
    print("Failed to read video")
     cap.release()
 prev_gray = cv2.cvtColor(prev_frame, cv2.COLOR_BGR2GRAY)
 prev_kp = fast.detect(prev_gray, None)
 prev_kp, prev_des = orb.compute(prev_gray, prev_kp)
 while cap.isOpened():
     ret, frame = cap.read()
     if not ret:
         break
     gray = cv2.cvtColor(frame, cv2.COLOR_BGR2GRAY)
     \ensuremath{\text{\#}} Detect keypoints with FAST and compute descriptors with ORB
     kp = fast.detect(gray, None)
     kp, des = orb.compute(gray, kp)
     # Match descriptors using BFMatcher
     if prev_des is not None and des is not None:
         bf = cv2.BFMatcher(cv2.NORM_HAMMING, crossCheck=True)
         matches = bf.match(prev_des, des)
         matches = sorted(matches, key=lambda x: x.distance)
         # Draw top matches
         match_img = cv2.drawMatches(prev_frame, prev_kp, frame, kp, matches[:20], None, flags=2)
         # Display output
         cv2_imshow(match_img)
     prev_frame = frame
     prev_gray = gray
     prev_kp = kp
     prev_des = des
 cap.release()
 cv2.destroyAllWindows()
```

- ••• Requirement already satisfied: opencv-python-headless in /usr/local/lib/python3.11/dist-packages (4.11.0.86)
 Requirement already satisfied: numpy>=1.21.2 in /usr/local/lib/python3.11/dist-packages (from opencv-python-headless) (2.0.2) Choose Files 2735069-u...0_15fps.mp4
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