Installation Instructions

The environment that I have my project working on has below softwares and installation steps:
- Native Ubuntu 20.04
- Python 3.8.10
- Python Virtual Environment (not required to run the program, I used it to segregate my Python environments)
- ROS2 Foxy (https://docs.ros.org/en/foxy/Installation.html)
- Opencv
  - sudo apt update
  - sudo apt install python3-opencv
- Numpy
  - sudo apt install python3-numpy
- djitellopy
  - pip install djitellopy
  - https://github.com/damiafuentes/DJITelloPy
- Retain 'haarcascade_frontalface_default.xml' where it is in the repo. If changing the location please provide the absolute path of it within 'opencv_node.py' for 'faceCascade' variable
- After cloning the repo on local perform a build using 'colcon build' and source the project using '. install/setup.bash'
- If testing on a drone connect to drone's network from computer and then run the launch file and override node from project root as below:
  - ros2 launch face_tracking_drone script.launch.py
  - ros2 run face_tracking_drone override_node
- Hitting 'q' at any time of flight from terminal running override_node would land the drone