The Physical system mainly involves the drone and raspberry Pi. We use a drone and dock a raspberry Pi with a NOIR camera onboard. The drone mainly consists of the frame, rotors, ESCs and battery. A Flight control board like a PIXHAWK can be attached to the ESCs for flight stability and controllability using python executables. A link from the flight control board can be established to an onboard microcontroller like raspberry Pi using wireless MAVLink protocol. The control of the PIXHAWK can be done from the raspberry Pi using the Drone-Core or Drone-kit python APIs. The NOIR raspicamera can be docked into the slot provided on the raspberry Pi. Furthermore, a GStream link can be setup over Wi-Fi from the raspberry Pi to a stationary workstation to monitor the stream that is being processed. A RC controller remote is also necessary so that it can intervene the drone movement md-flight to land it during any discrepancies or emergencies. Stereo or Mono camera could be integrated to the raspberry Pi via USB for distance to object in image calculation. The drone can also be communicated using ZigBee modules for manual intervention. The simulation can be performed using SITL and dronekit-SITL.