

[pcl::KdTreeFLANN::setInputCloud] Cannot create a KDT
ud!

Scene total points: 0; Selected Keypoints: 0

```
    scene_filename_ [ 191 // Publish the data  
    192 //pub.publish (output);  
    193 ]
```

Status 22:19:46: This is Geany 0.21.

Compiler 22:19:46: File /home/ameneh/catkin_ws/src/my_pcl_tutorial/src/cc

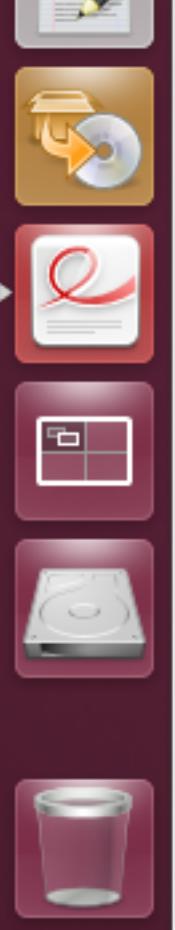
Messages 22:24:27: File /home/ameneh/catkin_ws/src/my_pcl_tutorial/src/cc

Scribble 22:25:20: File /home/ameneh/catkin_ws/src/my_pcl_tutorial/src/cc

Terminal 22:26:11: File /home/ameneh/catkin_ws/src/my_pcl_tutorial/src/cc

22:32:17: File /home/ameneh/catkin_ws/src/my_pcl_tutorial/src/cc

line: 183 / 492 col: 34 sel: 0 INS TAB mode: Unix (LF) encoding:



```
[stacks/roboearth] Updating /home/ameneh/ros/stacks/roboearth
At revision 3080.
[stacks/roboearth] Done.
[stacks/ccny_vision] Updating /home/ameneh/ros/stacks/ccny_vision
[stacks/ccny_vision] Done.
[pkgs/tum-ros-pkg/knowledge] Fetching https://tum-ros-pkg.svn.sourceforge.net/svnroot/tum-ros-pkg/knowledge
svn: Repository moved permanently to 'https://svn.codeweavers.com/svn/tum-ros-pkg/knowledge'
[stacks/knowrob] Updating /home/ameneh/ros/stacks/knowrob
[stacks/knowrob] Done.
[stacks/knowrob_addons] Updating /home/ameneh/ros/stacks/knowrob_addons
[stacks/knowrob_addons] Done.
Exception caught during install: Error processing 'pkgs/tum-ros-pkg/knowledge' version None into '/home/ameneh/ros/stacks/knowrob'

ERROR in config: Error processing 'pkgs/tum-ros-pkg/knowledge' version None into '/home/ameneh/ros/stacks/knowrob'
```

ameneh@ameneh-VPCEG3BFX:~/ros\$



```
2567d60scene0x2567d60scene0x2567d60scene0x2567d60scene0x2567d60scen  
7d60scene0x2567d60scene0x2567d60scene0x2567d60scene0x2567d60scene0x  
0scene0x2567d60scene0x2567d60scene0x2567d60scene0x2567d60scene0x256  
ene0x2567d60scene0x2567d60scene0x2567d60scene0x2567d60scene0x2567d6  
0x2567d60scene0x2567d60scene0x2567d60scene0x2567d60scene0x2567d6  
567d60scene0x2567d60scene0x2567d60scene0x2567d60scene0x2567d60scen  
width: 640  
height: 480  
is_dense: 0  
sensor origin (xyz): [0, 0, 0] / orientation (xyzw):  
  
scene0x2567d60scene0x2567d60scene0x2567d60scene0x2567d60scen  
ne0x2567d60scene0x2567d60scene0x2567d60scene0x2567d60scen  
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