

Abstract

An image processing device detects, with respect to a frame image, feature points #1, #2 for measuring
5 a dimension which are feature points in side surfaces of a vehicle, and a feature point #3 for measuring the dimension which is a feature point on a bottom surface, and calculates a width of the vehicle by performing a motion stereo process on the feature points #1, #2, #3.
10 Positions of the feature points #1 to #3 to be detected by the image processing device are detected such that the positions of the feature points are arbitrary in the side surfaces or the bottom surface of the vehicle.