

Automotive Particulate Matter and Gaseous Emission Factors from On-Road Measurement in Las Vegas, NV

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NARSTO Emission Inventory Workshop
October 14-17, 2003, Austin, Texas



Acknowledgments



- **Coauthors.**
- **Dan Wermers, Rick Purcell, Larry Sheetz, DRI Facilities.**
- **Vicken Etyemezian, and Ali Yimer.**
- **Federal Transit Administration (Contract 26-70030), Clark County, NV (Contract C1062-99-item 26), DoD SERDP (Contract CP-1336), Coordinating Research Council (Contract E56-1), Desert Research Institute.**

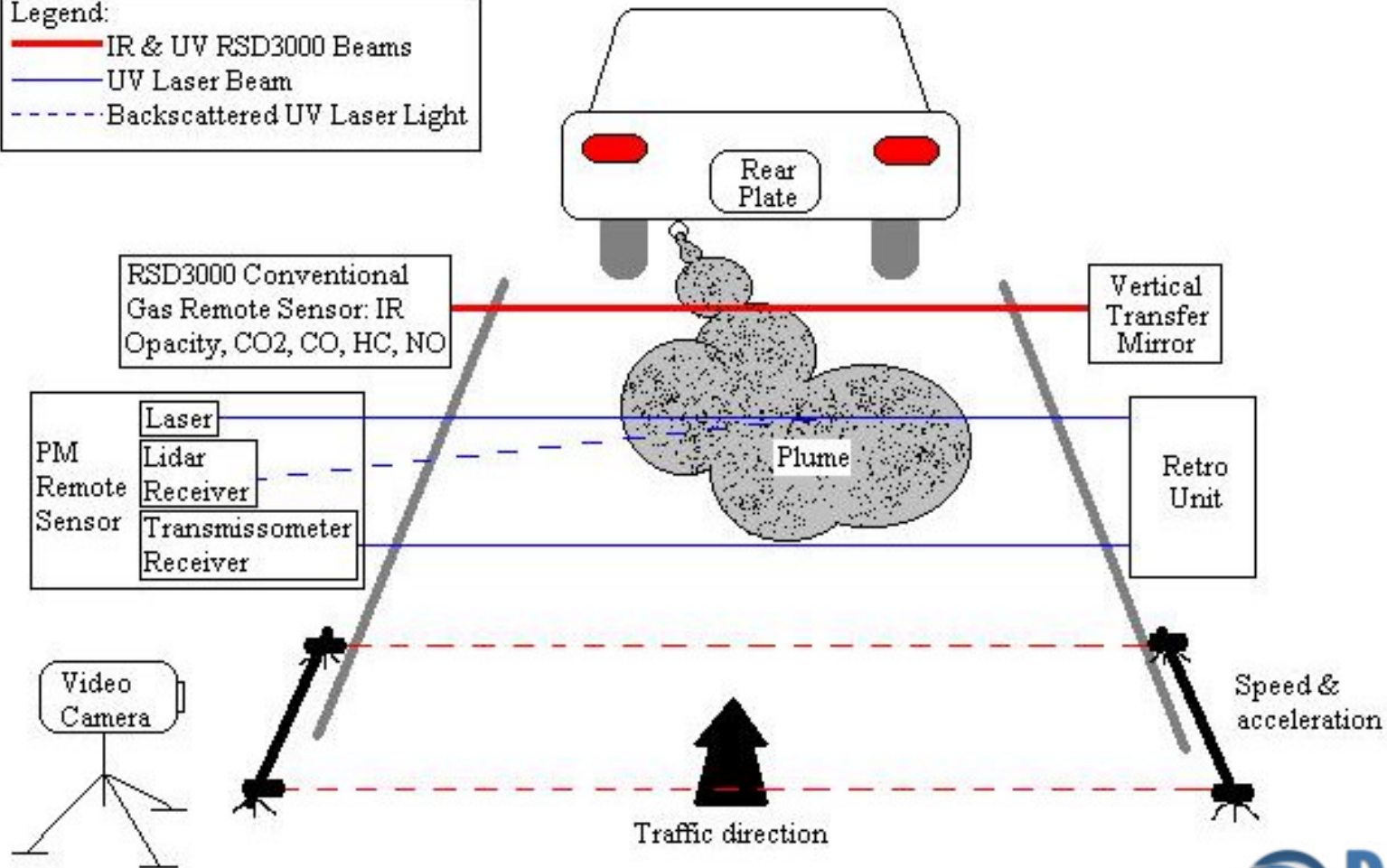
Outline

- Vehicle Emission Remote Sensing Systems:
 - Commercial gaseous remote sensor
 - Newly developed PM remote sensor
- Las Vegas, NV experiment
- Results
- Conclusions



Principles of Remote Sensing Systems

Legend:
— IR & UV RSD3000 Beams
— UV Laser Beam
- - - Backscattered UV Laser Light



See poster by Hans Moosmüller et al.

Advantages and Limitations of Remote Sensing

Advantages:

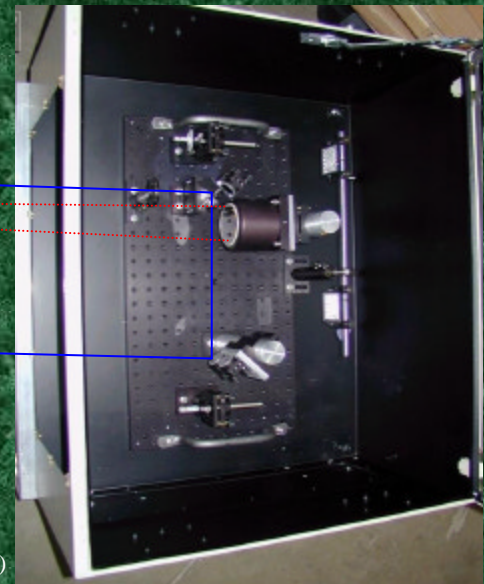
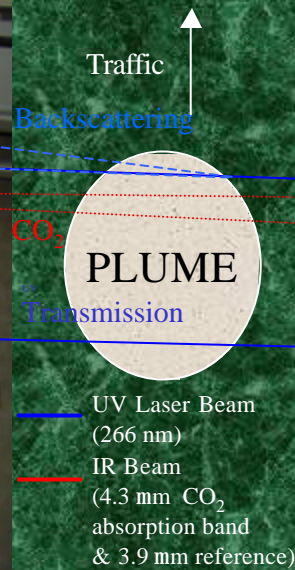
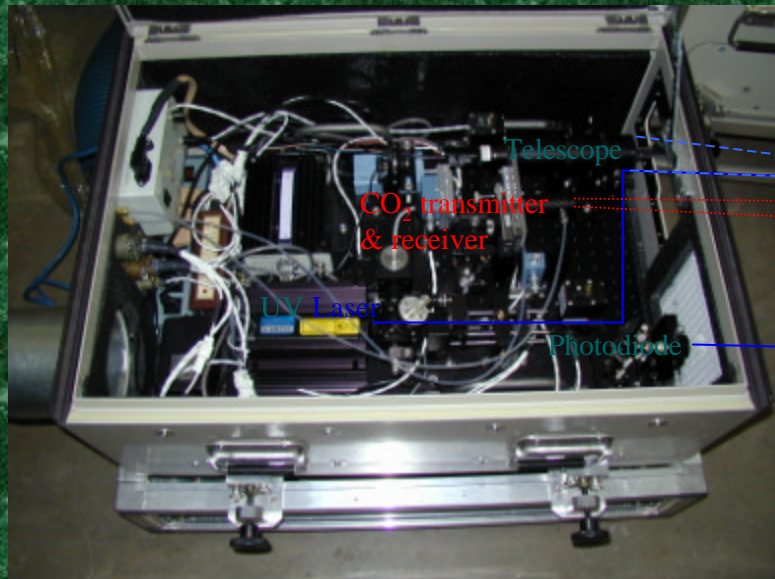
- **Large amount of vehicles measured (good fleet representation).**
- **Excellent vehicle selectivity. Each vehicle identified by rear plate. Fuel type, vehicle weight category, model year, origination are known.**
- **Low cost per vehicle, non invasive.**

Limitations:

- **Instantaneous emission (0.5 sec.).**
- **Limited operating conditions.**
- **Limited measurements techniques.**



PM & Gaseous Remote Sensing System



Fuel Based Emission Factors Calculation

- Pollutant column density: ρ_{c_P}
- Emission factor [grams_P/kg_{fuel}]:

$$EF_P = CMF_{fuel} \frac{\frac{\mathbf{r}_{c_P}}{\mathbf{r}_{c_CO2}}}{CMF_{CO2} + \left(CMF_{CO} \frac{\mathbf{r}_{c_CO}}{\mathbf{r}_{c_CO2}} + CMF_{HC} \frac{\mathbf{r}_{c_HC}}{\mathbf{r}_{c_CO2}} \right)}$$

Where CMF = carbon mass fraction

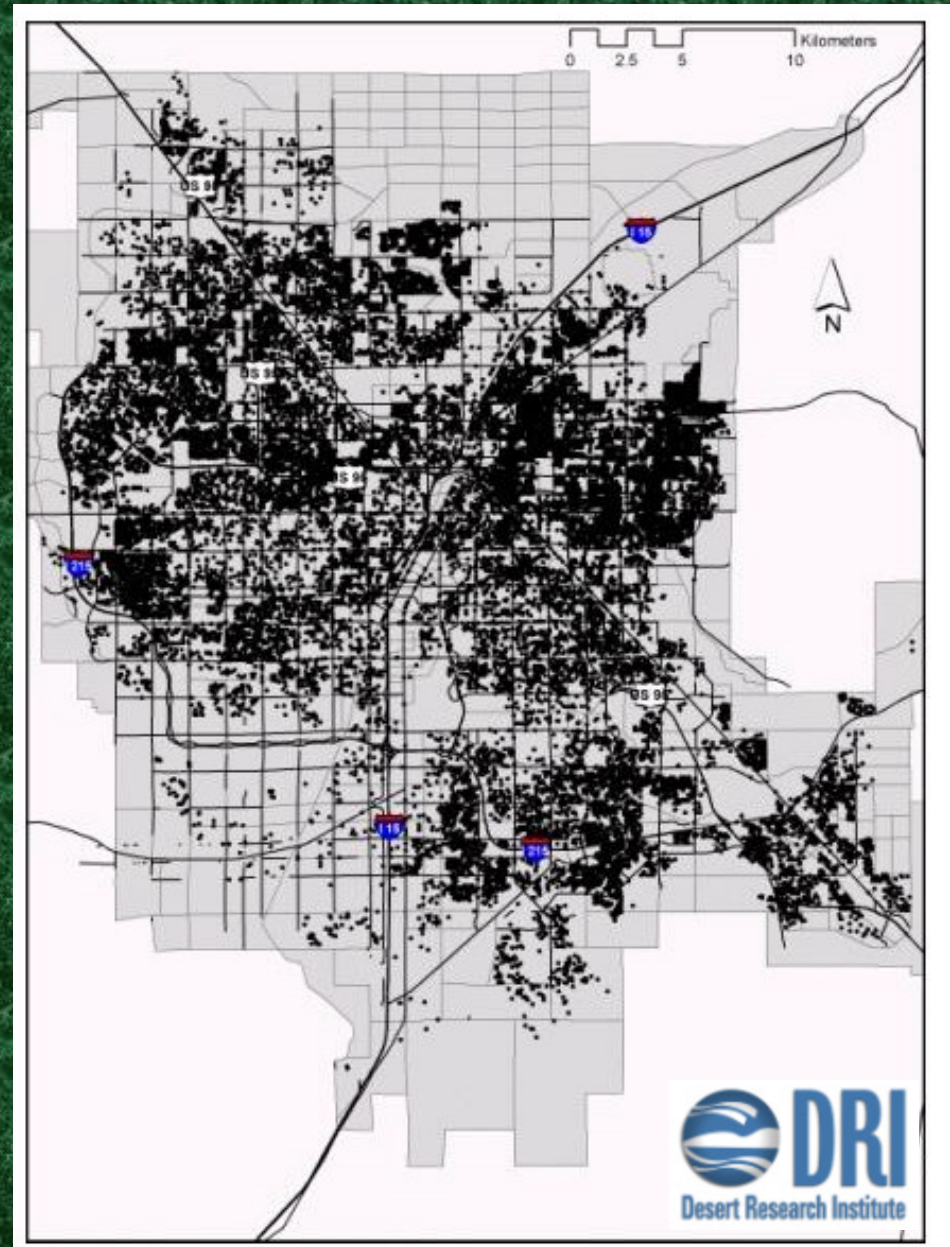


Current PM Remote Sensor Limitations:

- Data acquisition system too slow to fully take advantage of the signal available.
- No overlap between CO₂ and PM beams.
- Absence of built-in CO, HC and NO remote sensors.

Las Vegas Experiment

Black dots: location of registered ownership for remotely sensed light duty gasoline vehicles in Clark County (2000-2002).



Number of Measured Vehicles in Las Vegas, NV

	Number of Matched License Plates With Valid CO₂	CO	HC	NO	PM
2000	22152	22130	21831	21155	Not measured
2001	10188	10030	9914	9660	6047
2002	9561	9409	9249	8716	8768
Detection limits in g_{Pollutant}/Kg_{Fuel}		5	1	1	0.3

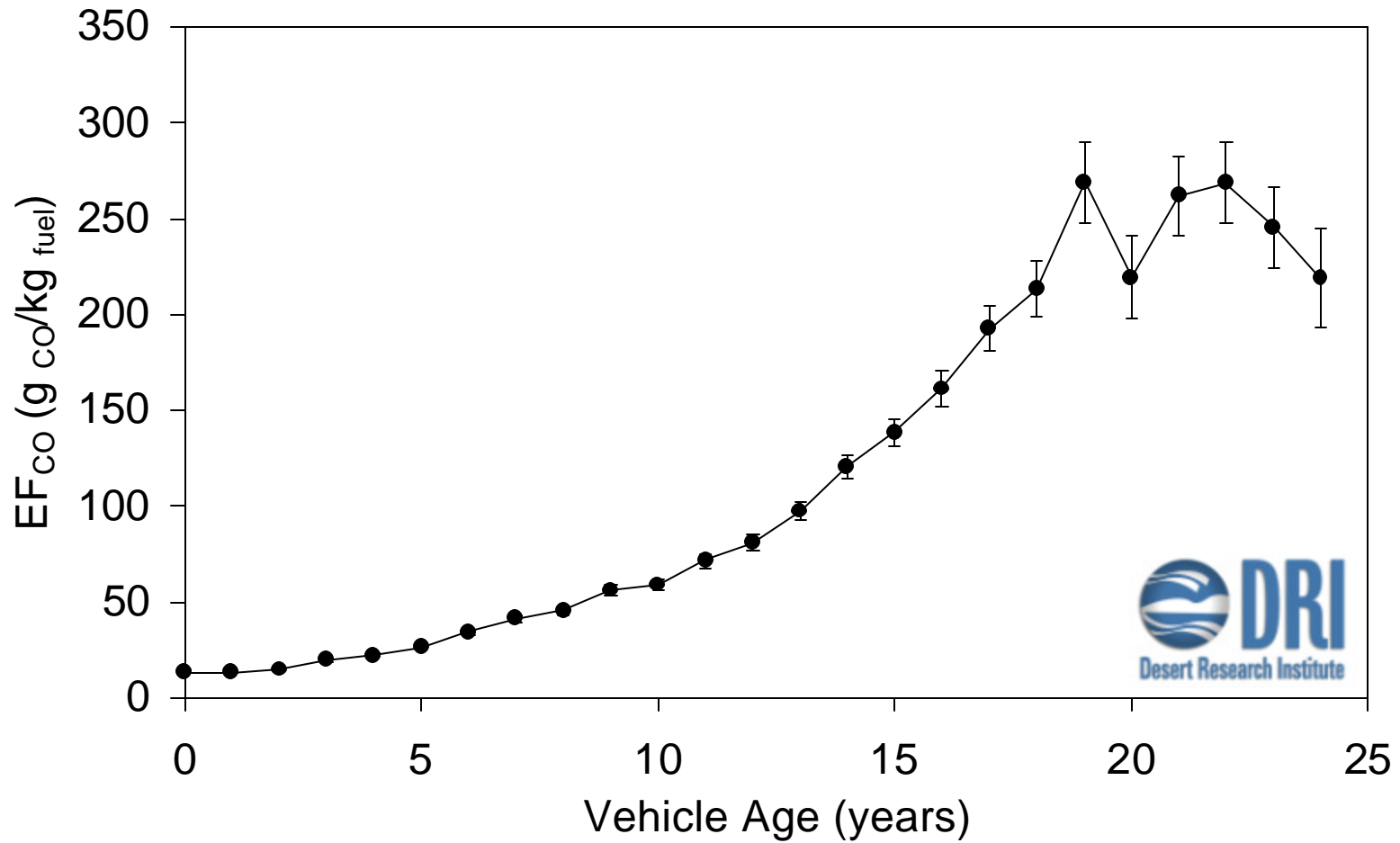
Fleet Average Emissions



Vehicle Type	CO (g _{CO} /Kg _{Fuel})	HC (g _{HC} /Kg _{Fuel})	NO (g _{NO} /Kg _{Fuel})	PM (g _{PM} /Kg _{Fuel})
LDGV	49	2.8	8.8	0.06
LDDV	19	2.3	15.2	1.6
HDGV	56	2.6	10.3	0.05
HDDV	10	1.6	19.9	1.5

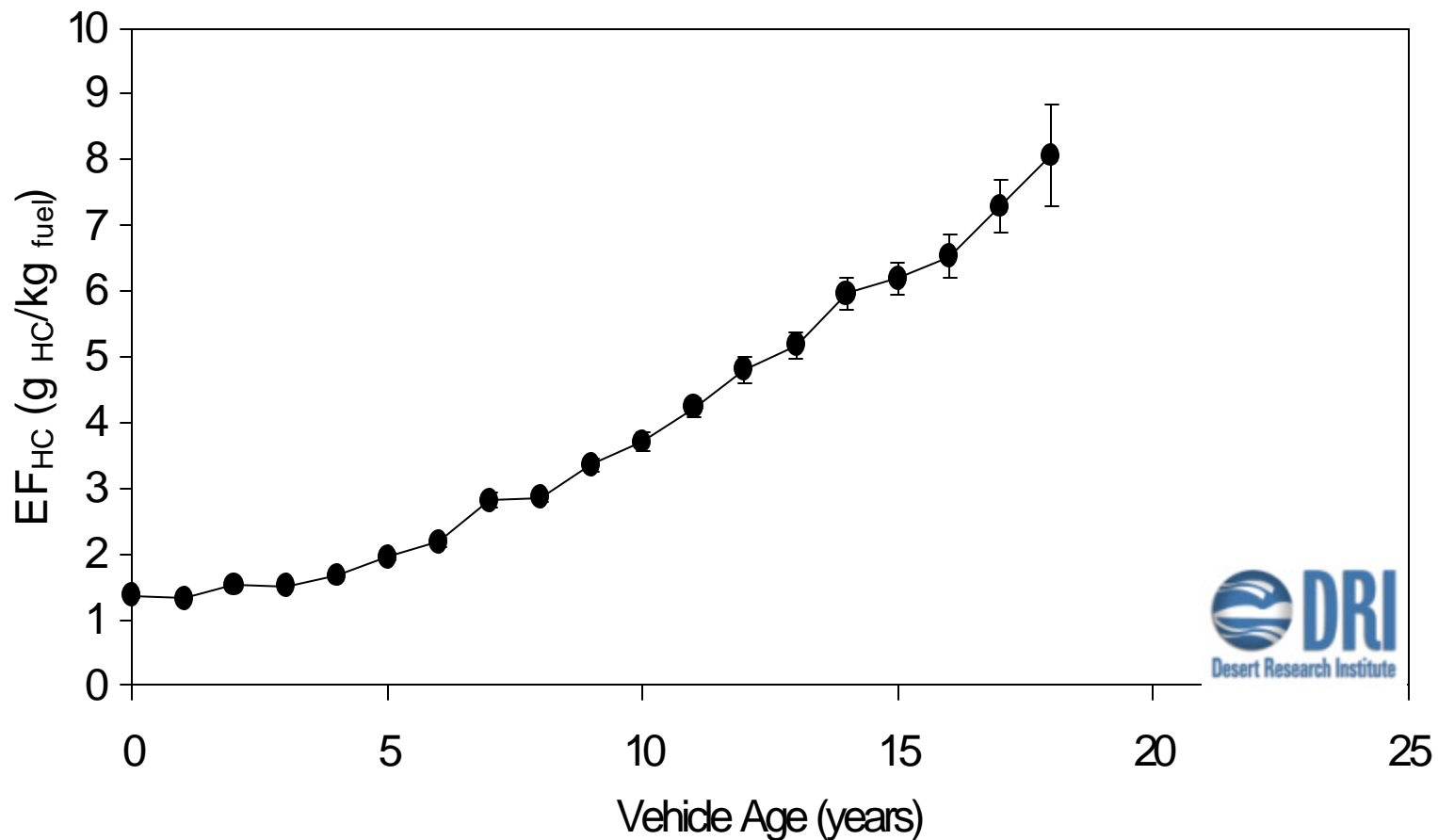
CO Emission with Age

LDGV VERSS



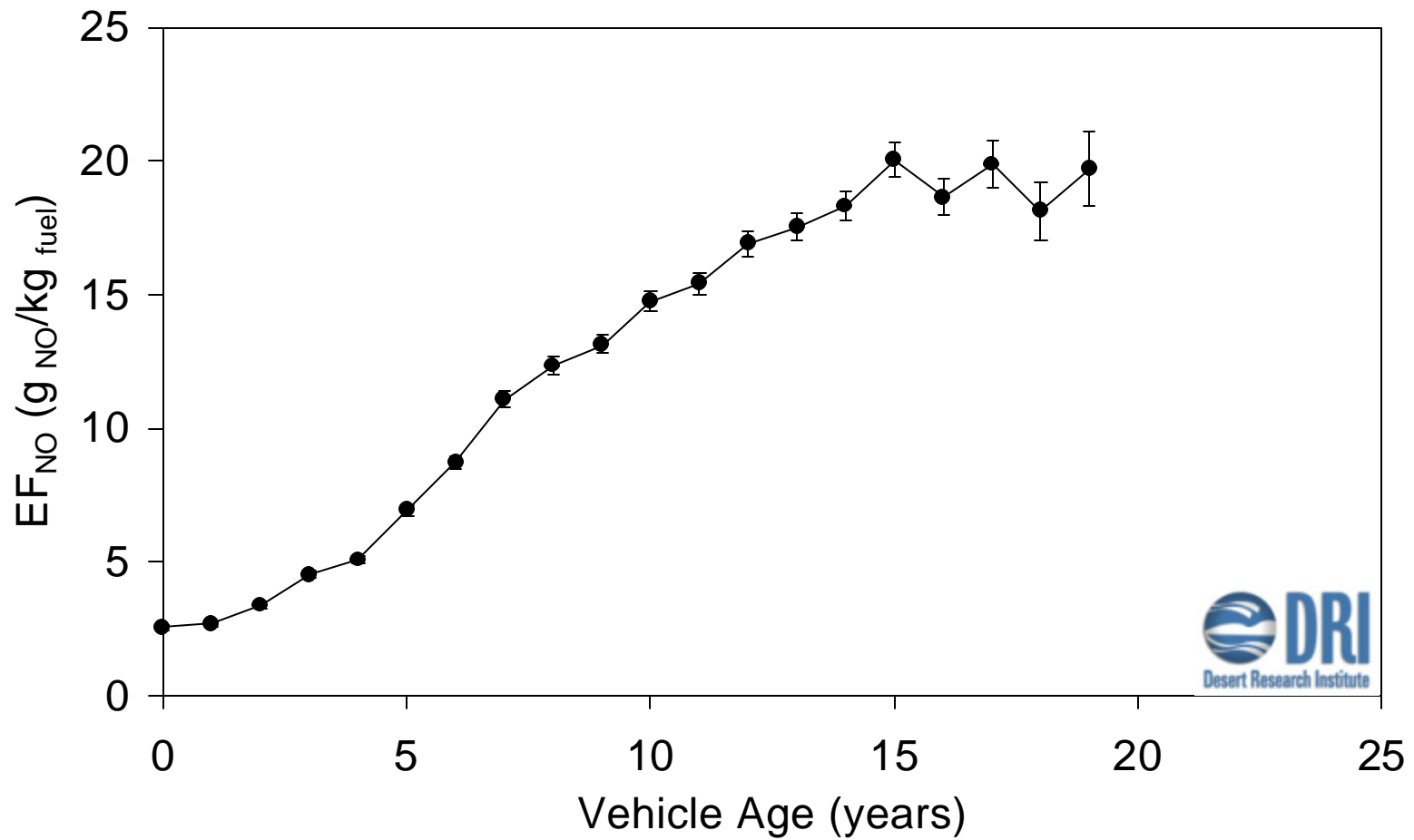
HC Emission with Age

LDGV VERSS



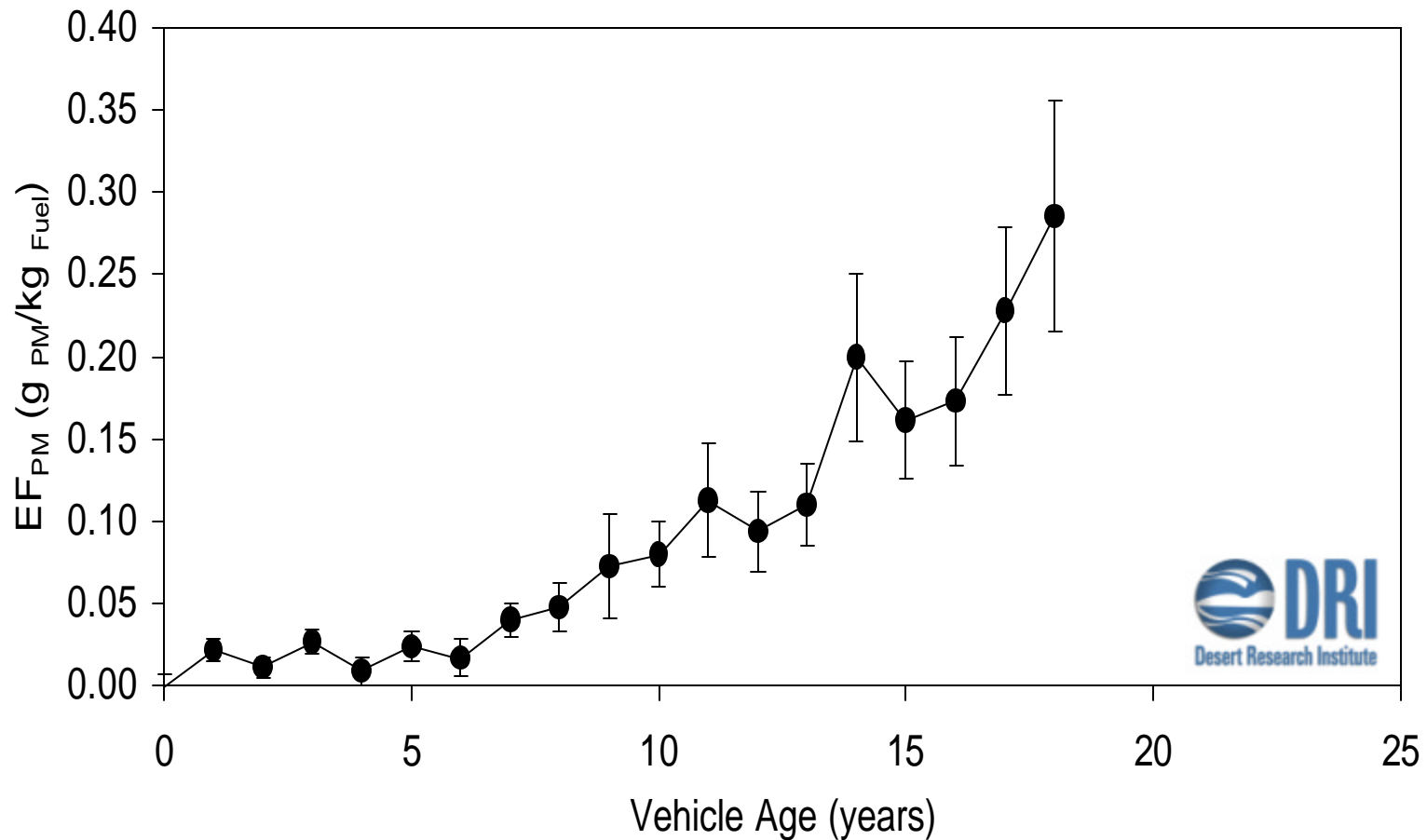
NO Emission with Age

LDGV VERSS

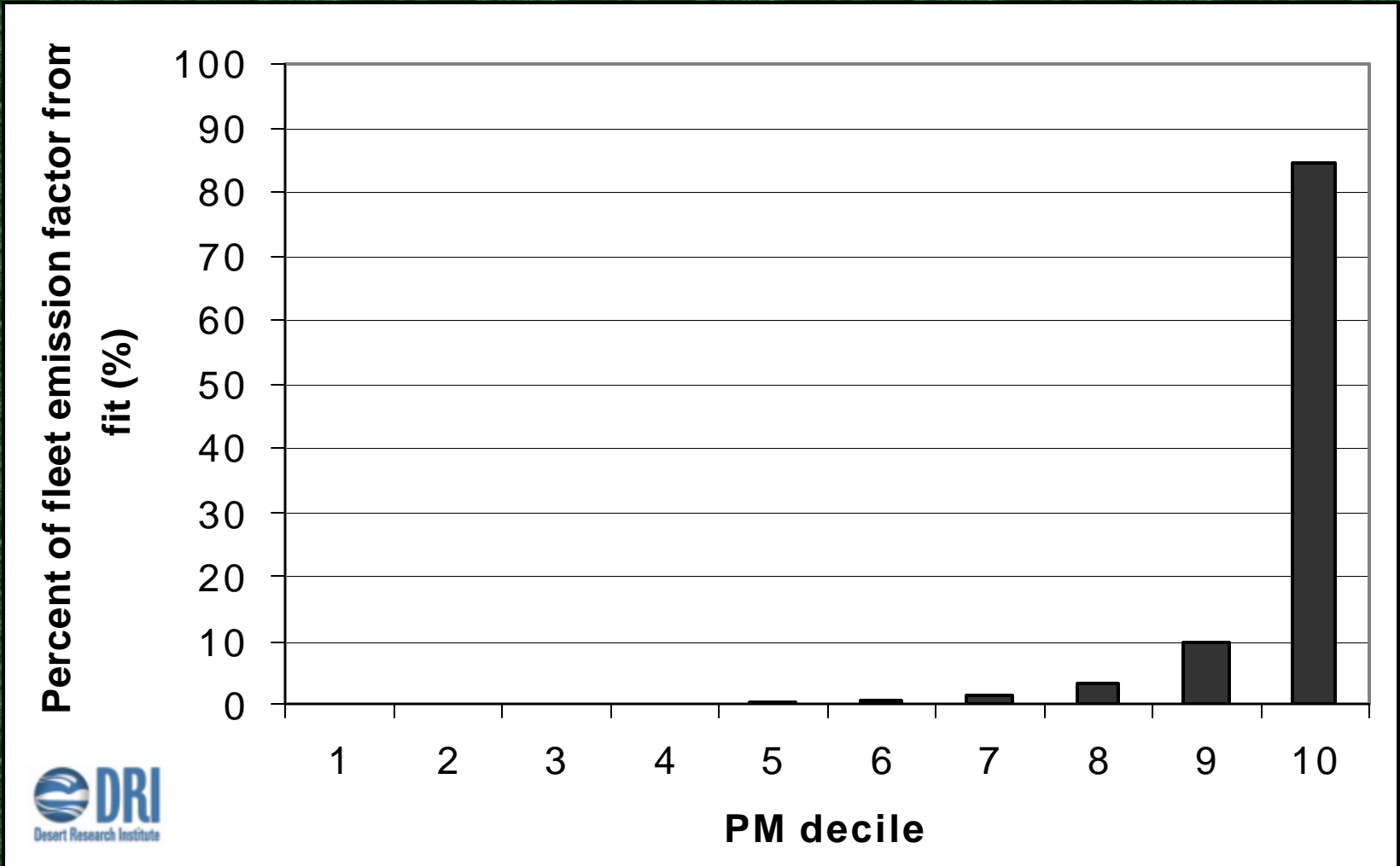


PM Emission with Age

LDGV VERSS



Deciles Plot of Fitted Fleet Emission Distribution



Distributions Summary



Measure type	Distributions: Noise Emission	Contribution to fleet emission factor by highest 10% of emitters From fit
UV Backscattering PM	DE W	> 82 %
UV Transmission PM	DE W	> 85 %
CO	DE G	75 %
HC	DE W	49 %
NO	DE G	47 %

Overlap Between Different Pollutants

	Number Of Vehicles	Fraction Of Measured Fleet
Total number of vehicles	15237	
No high emitters in any category	11024	72.35%
High emitters in one category		Total: 18.20 %
CO	618	4.06%
HC	365	2.40%
NO	899	5.90%
PM	891	5.85%
High emitters in two categories		Total: 6.83 %
CO & HC	474	3.11%
CO & NO	53	0.35%
CO & PM	67	0.44%
HC & NO	210	1.38%
HC & PM	84	0.55%
NO & PM	151	0.99%
High emitters in three categories		Total: 2.36 %
CO & HC & NO	70	0.46%
CO & HC & PM	190	1.25%
CO & NO & PM	10	0.07%
HC & NO & PM	89	0.58%
Highest emitters in all four categories	42	0.28 %

Future Improvements

- Increase signal to noise ratio
 - Higher acquisition rate
 - Larger collection system
 - Increased detector sensitivity
 - Increased laser power
- Built-in gaseous detection and improved collinearity
- On-road comparison with other measurement techniques

Conclusions

- PM remote sensor was used to determine on-road fleet average PM emissions.
- PM emissions increase with vehicle age.
- PM emission distribution is highly skewed with more than 80% of the total PM fleet emission factor due to only 10% of highest emitters.
- Low overlap was found between highest emitters groups for different pollutants.
- Current PM LIDAR system has limited sensitivity for individual low emitters, but can detect individual gross PM polluters.
- Software and hardware redesign is in progress and will greatly increase the signal to noise ratio.

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