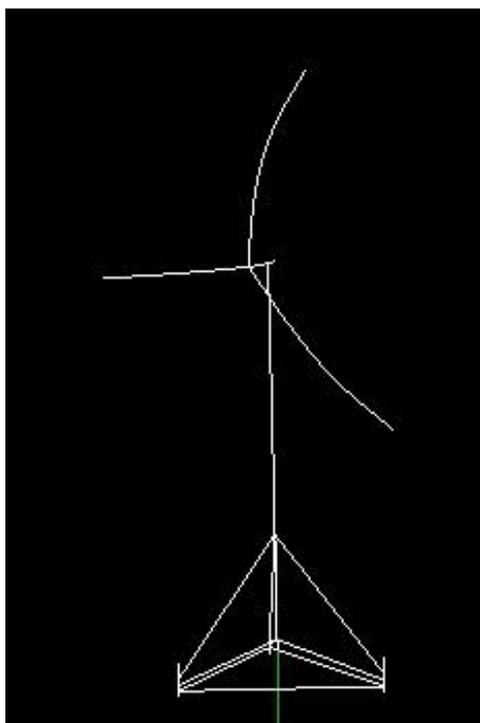


## How 2 HAWC2, the user's manual

Torben Juul Larsen, Anders M. Hansen

Risø-R-1597(ver. 4-6)(EN)



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**Abstract (max. 2000 char.):**

The report contains the user's manual for the aeroelastic code HAWC2. The code is intended for calculating wind turbine response in time domain and has a structural formulation based on multi-body dynamics. The aerodynamic part of the code is based on the blade element momentum theory, but extended from the classic approach to handle dynamic inflow, dynamic stall, skew inflow, shear effects on the induction and effects from large deflections. It has mainly been developed within the years 2003-2006 at the aeroelastic design research programme at Risoe, National laboratory Denmark, but is continuously updated and improved.

This manual is updated for HAWC2 version 12.2 and wkin.dll version 2.2

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## Preface

The HAWC2 code is a code intended for calculating wind turbine response in time domain. It has been developed within the years 2003-2006 at the aeroelastic design research programme at Risø, National laboratory Denmark.

The structural part of the code is based on a multibody formulation where each body is an assembly of timoshenko beam elements. The formulation is general which means that quite complex structures can be handled and arbitrary large rotations of the bodies can be handled. The turbine is modeled by an assembly of bodies connected with constraint equations, where a constraint could be a rigid coupling, a bearing, a prescribed fixed bearing angle etc. The aerodynamic part of the code is based on the blade element momentum theory, but extended from the classic approach to handle dynamic inflow, dynamic stall, skew inflow, shear effects on the induction and effects from large deflections. Several turbulence formats can be used. Control of the turbine is performed through one or more DLL's (Dynamic Link Library). The format for these DLL's is also very general, which means that any possible output sensor normally used for data file output can also be used as a sensor to the DLL. This allows the same DLL format to be used whether a control of a bearing angle, an external force or moment is placed on the structure.

The code has internally at Risø been tested against the older validated code HAWC, the CFD code Ellipsys and numerous measurements. Further on detailed verification is performed in the IEA annex 23 and annex 30 research project regarding offshore application. Scientific papers involving the HAWC2 is normally posted on the [www.hawc2.dk](http://www.hawc2.dk) homepage, where the code, manual and more can be downloaded.

During the programming of the code a lot of focus has been put in the input checking so hopefully meaningful error messages are written to the screen in case of lacking or obvious erroneous inputs. However since the code is still constantly improved we appreciate feedback from the users – both good and bad critics are welcome.

The manual is also constantly updated and improved, but should at the moment cover the description of available input commands.

## Acknowledgements

The code has been developed primarily by internal funds from Risø National Laboratory – Technical University of Denmark, but the research that forms the basis of the code is mainly done under contract with the Danish Energy Authority.

The structural formulation of the model is written by Anders M. Hansen as well as the solver and the linking between external loads and structure. The anisotropic FPM beam model is written by Christian Pavese, Taeseong Kim and Anders M. Hansen. The aerodynamic BEM module is written by Helge A. Madsen and Torben J. Larsen. Three different stall models are implemented where the S.Ø. (Stig Øye) model is implemented by Torben J. Larsen, the mhh Beddoes model is written by Morten Hansen and Mac Gaunaa and the ateflap model used for trailing edge flaps is written by Mac Gaunaa and Peter Bjørn Andersen and has later been rewritten by Leonardo Bergami. The wind and turbulence module as well as the soil and DLL modules are written by Torben J. Larsen. The hydrodynamic module is written by Anders M. Hansen and Torben J. Larsen. The turbulence generator is written by Jacob Mann and the WAsP Team and converted into a DLL by Peter Bjørn Andersen. The dynamic wake meandering module is written by Helge A. Madsen, Gunner Larsen and Torben J. Larsen. The eigenvalue solver is implemented by Anders M. Hansen and John Hansen. General maintenance is performed by Torben J. Larsen and Anders M. Hansen. The web page [www.hawc2.dk](http://www.hawc2.dk) is maintained by Anders Yde.

## General input layout

The HAWC 2 input format is written in a form that forces the user to write the input commands in a structured way so aerodynamic commands are kept together, structural commands the same etc.

The commands are divided into command blocks using the begin-end syntax. Each line has to be ended with a semi colon “;” which gives the possibility for writing comments and the end of each line after the semi colon. All command lines can be written with capital or small letters, but inside the code all lines are transformed into small letters. This could have importance if something case sensitive is written (e.g. the name of a subroutine within a DLL).

```
begin simulation;
  time_stop  100.0 ;
  solvetype  1 ;   (newmark)
;
  begin newmark;
    beta      0.27;
    gamma     0.51;
    deltat    0.02;
  end newmark;
end simulation;
```

In the next chapters the input commands are explained for every part of the code. The notation is main command for a begin-end command block that is not a sub part of another begin-end block, and sub command block for a begin-end block that is included within another block. In the above written example “simulation” is a main command block and “newmark” is a sub command block.

### Continue\_in\_file option

A feature from version 6.0 and newer is the possibility of continuing reading of the main input file into another. The command word **continue\_in\_file** followed by a file name causes the program to open the new file and continue reading of input until the command word **exit**. When **exit** is read the reading will continue in the previous file. An infinite number of file levels can be used.

Command name	Explanation
continue_in_file	1. File name (and path) to sublevel input file
exit	End of input file. Input reading is continued in higher level input file.

## **HAWC2 version handling**

The HAWC2 code is still frequently updated and version handling is therefore of utmost importance to ensure quality control. For every new released version of the code a new version number is hard coded in the source. This number can be found by executing the HAWC2.exe file without any parameters. The version number is echoed to screen. The same version number is also written to every result file no matter whether ASCII or binary format is chosen. Hereby it is possible to reproduce all results at later stage and to dig in the source code for at previous version if special problems occur.

All information covering the different code versions has been made. These data are listed on the next pages.

# Risø DTU

!	Version information:	!	Date	Resp	Info
!	Version name	!			
!-----					
! global%version='HAWC2MB 1.0'!	20.04.2006	TJUL			Version system started. Changes in so_dyn_stall model performed.
!	!	24.04.2006	TJUL/ANMH	Bearing3	in topology - slight modification still needed, but now maha needs a version
! global%version='HAWC2MB 1.1'!	25.04.2006	TJUL			maha laptop in MAC check, integer overflow negletec in compiler settings
! global%version='HAWC2MB 1.1work'	!	26.04.2006	TJUL		tjul stationairy pc in MAC check
!	!	!			New check regarding thicknesses in aeodynamic files
!	!	28.04.2006	TJUL		ktho stationairy pc in MAC check
! global%version='HAWC2MB 1.2'!	28.04.2006	TJUL			Radius non-dim in structural _st input data and aerodynamic _ae data
! global%version='HAWC2MB 1.3'!	01.05.2006	TJUL			Extra check in structural files reading procedures
!	!	!			Tab characters can now be used in htc files and other input files
!	!	!			Check that c2_def structure length larger than eps
! global%version='HAWC2MB 1.4'!	02.05.2006	TJUL			New check in hawc_file output that time_stop>time_start
!	!	!			Topologi_timoschenko.f90 updated related to changes in version 1.3
! global%version='HAWC2MB 1.5'!	03.05.2006	TJUL			ktho laptop in MAC check
!	!	!			Get_state_rot function in body.f90
!	!	!			New mbdy state_rot output command in topologi_mainbody_output
!	!	!			Rotation velocity and acceleration in aerodynamic blade section variables
!	!	!			MACQ/TJUL Dynamic_stall_mhh included
! global%version='HAWC2MB 1.6'!	04.05.2006	TJUL			Extension of bladelink criteria for execution stop
! global%version='HAWC2MB 1.7'!	09.05.2006	TJUL			New error message in windturb_mann.f90
!	!	!			New error messages regarding matrix not definite problems
!	!	!			New MAC checks (Niels Kjølstad + students)
! global%version='HAWC2MB 1.8'!	09.05.2006	TJUL			New MAC check
! global%version='HAWC2MB 1.9'!	16.05.2006	TJUL			New MAC check
! global%version='HAWC2MB 2.0'!	18.05.2006	TJUL			New MAC check
! global%version='HAWC2MB 2.1'!	19.05.2006	TJUL			Error messages corrected in mbdy state_rot command
!	!	!			MHHA/TJUL New MAC check procedure (loop over all adresses instead of only one)
! global%version='HAWC2MB 2.2'!	22.05.2006	TJUL			New ignore function in body actions
!	!	30.05.2006	TJUL		Old MAC check procedure reimplemented since troubles occured with the new version
! global%version='HAWC2MB 2.3'!	30.05.2006	TJUL			Replacement of procedure that calculates euler parameters based on transformation matrix
!	!	!			(only important for cases with eulerp output used)
! global%version='HAWC2MB 2.4'!	31.05.2006	TJUL			General cleanup in multibodyproto.f90 file (simple generator model excluded, now
!	!	!			tmp_gen_speed output command is excluded)
!	!	01.06.2006	TJUL		New MAC checks
! global%version='HAWC2MB 2.5'!	04.06.2006	TJUL			External Licence manager DLL used. Avoids new versions of the HAWC2 code to be build at
!	!	!			every new MAC number
!	!	!			and and also works when the computer is not connected to a LAN
! global%version='HAWC2MB 2.6'!	13.06.2006	TJUL			Newmark variables reorganized
!	!	!			Hydrodynamic loads cut-in at 2secs, as for the aero loads. To reduce initial transients
!	!	!			New acceptance criteria from License manager
!	!	!			New input check in topologi_mainbody
!	!	!			Order of radius of gyration input shifted for the new_htc_structure input. Now: 1 <sup>st</sup>
!	!	!			column (Rix) is the one affected if mass center position changes on the chord line
! global%version='HAWC2MB 2.7'!	23.06.2006	ANMH			Normalisation of vectors in utils funtions get_two_plane_vectors. Used for better

!				accuracy in bearing1 and bearing2 definitions
!	global%version='HAWC2MB 2.8'!	17.07.2006	TJUL/FRBA	Correction of bug in get_ae_data procedure in aeroload_calcforces unit. Profile sets higher than one is now also usable.
!	global%version='HAWC2MB 2.9'!	17.07.2006	TJUL	Gravity loads cut-in at 0.5secs, same method as for the aero loads. To reduce initial transients
!	global%version='HAWC2MB 3.0'!	24.07.2006	TJUL	Harmonic2 function in general output (time limited harmonic function) topologi_mainbody_actions module added. New features to the actions list.
!	global%version='HAWC2MB 3.1'!	26.07.2006	TJUL	Mann turbulence is reused if simulation time is longer than included in turbulence box
!	global%version='HAWC2MB 3.2'!	28.07.2006	TJUL	Correction of bug in aerodynamic moment integration procedure (only related to aerodynamic file output)
		31.07.2006	TJUL	Change of error message criteria regarding allowable number of bodies within a mainbody (<n elements)
		01.08.2006	TJUL	Correction of bug in dynstall_mhh model so no division by zero occurs when a zerolift profile is used.
		01.08.2006	ANMH	Correction of bug related to torsion of blade in the blade linker
!	global%version='HAWC2MB 3.3'!	04.08.2006	TJUL	Check applied on exp expressions in dynamic stall mhh model to avoid underflow errors
!	global%version='HAWC2MB 3.4'!	09.08.2006	TJUL	New check applied in mann turbulence unit to avoid array out of bounds during bizar startup transients
!		11.08.2006	TJUL	Correction of exp check in dynstall_mhh model just created in version 3.2
!	global%version='HAWC2MB 3.5'!	28.08.2006	TJUL	Generator_rotation sensor setup for old_htc_structure format - replaces the older tmp_gen_speed sensor. Updates in hawcstructure.f90 and body_output.f90
!				New error message in body_output
!				Improvement of general command reader in genout_tools in order to accept tabulator spacings
				General shine up of aerodynamic calculations regarding induction and tiploss calculations rechecked against IEA rev 3 calculations
				Number of radial point in the induction calculation is default set to the name number as number of aero sections. Previous default of 30 stations
				Linear interpolation in aeroload_tools updated so no division by zero occurs when x0=x1, used in cases where extrapolation is not wanted
		29.08.2006	ANMH/TJUL	Fix1 constraints updated in topologi_constraints_fix1.f90 and hawcstructure.f90. Ensures e.g. that constraint properties are identical for blades. Ensures that blades performs identically.
!	global%version='HAWC2MB 3.6'!	14.09.2006	TJUL	New acceptance criteria from license manager
!	global%version='HAWC2MB 3.7'!	15.09.2006	TJUL	New general load linker that replaces bladelink.f90 and wavelink.f90
			ANMH/TJUL	Pitchsensors (bearing sensor) updated during iterations too. Especially important for DLL controllers
!	global%version='HAWC2MB 3.8'!	06.10.2006	TJUL	Correction of bug related to aero int_force and int_moment sensors
				Correction of bug in DLL actions. On nodes different from nr. 1, in- and external forces and moments were placed on the node 1 number lower.
			TJUL	Pitch sensor modified. Now pitch velocity is calculated based on numerical differentiation of calculated angle. Should be less sensitive to solver inaccuracies.
			TJUL	In output of bearing sensor new options are added. (-180:180 deg output etc.)
			ANMH	Correction of bug in loadlinker. It turned out that loadfunction were only correct if an even number of calculation points were used (aero or hydro). Now OK also for odd numbers
!	global%version='HAWC2MB 3.9'!	06.10.2006	TJUL	Soil spring module added (soil stuff from hydro module removed)
!	global%version='HAWC2MB 4.0'!	02.11.2006	TJUL	Extra output commands in aero output_at

!	global%version='HAWC2MB 4.1'!	02.11.2006	ANMH/TJUL	Replacement of added stiffness method for soil springs. Much better and faster than previous. Still not perfect.
		!	10.11.2006	ANMH/TJUL Update of bearing3. Now it is general.
		!	10.11.2006	TJUL Output variables rearranged. Only command included in bearing outputs
		!	10.11.2006	TJUL Topologi input modified so many bases are allowable.
		!	15.11.2006	ANMH/TJUL Files synchronized with Anders. Slight update in dll_calls,dll_types and windturb_mann.
!	global%version='HAWC2MB 4.2'!	16.11.2006	TJUL	Rearrangement of output/action sensor allocation. Reduces .exe size from 23MB to 2.3MB
		!		TJUL/HAMA Correction of sensors induc and windspeed in output_at aero. They were previously in a wrong coordinate system when written to output_at.
!	global%version='HAWC2MB 4.3'!	17.11.2006	TJUL	New fix3 constraint. Locks a node to ground in a given rotation direction.
		!	23.11.2006	ANMH Update of loadlinker with respect to procedures for numerical update of stiffness, damping and mass terms. Improves solutions of soil spring systems significant.
		!	27.11.2006	TJUL Same procedure used for the hydrodynamic part => faster convergence.
!	global%version='HAWC2MB 4.4'!	27.11.2006	TJUL	Bug fixed related to input for action sensor: mbdy moment_int
		!	04.12.2006	ANMH index+7 -> index+6 in body_get_state_rot subroutine. Affects orientation of all local load elements in load linker.
!	global%version='HAWC2MB 4.5'!	06.12.2006	TJUL	New sensors in aero module.
		!		Out of bounds bug in aero output_at corrected
		!	07.12.2006	ANMH Files used in topologi_tools are closed after use.
		!	12.12.2006	TJUL In make output command, outputs are bypassed if global time > output stoptime
		!	13.12.2006	TJUL In mann turbulence a new command (dont_scale) is made.
		!	21.12.2006	TJUL Update of HAWC_mann module. Important only if turbulence outside box is used.
		!	04.01.2007	TJUL omega vector for aerodynamic module in rotor reference coordinates. In aero files only rotation speed around y-axis is used. Eliminates influence from e.g. pitch velocity
		!	04.01.2007	MHHA/TJUL New optional relaxation parameter for solver. Extra command in simulation input.
!	global%version='HAWC2MB 4.6'!	12.01.2007	ANMH	Change of sign in forceddll.f90. Important only if an external force dll as coupled springs are used. Not important for hawc_dll
!	global%version='HAWC2MB 4.7'!	06.02.2007	ANMH/TJUL	Update of code structure, multibodyproto split into several subroutines
		!		New logical variables related to simulation_input
		!		New state_at in mbdy output
!	global%version='HAWC2MB 4.8'!	08.02.2007	TJUL	mbdy actions force/moment commands updated with sign possibility on force component
!	global%version='HAWC2MB 4.9'!	12.02.2007	TJUL	new error message in turbulence input reader
		!	19.02.2007	TJUL New potential flow tower shadow model where source is linked to tower motion
	global%version='HAWC2MB 5.0'!	26.02.2007	TJUL	New mbdy state_rot output option: orientation in euler angles defined through the rotation order xyz
!	global%version='HAWC2MB 5.1'!	27.02.2007	TJUL	Correction of method used to calculate mbdy state_rot rotation in general
		!		New mbdy state_rot output option: orientation in euler angles defined through the rotation order yxz
		!		Small adjustments in DLL_output to avoid array out of bounds when long mbdy names are used
!	global%version='HAWC2MB 5.2'!	02.03.2007	ANMH/TJUL	Bug fixed related to continue_on_no_convergence criteria
		!		TJUL HAWC2MB version echoed to screen before input is read.
		!		TJUL New licence manager compiler option
!	global%version='HAWC2MB 5.3'!	13.03.2007	ANMH/TJUL	Bug fixed related to bearing3. Somehow the coupling nodes was not defined since version 4.0 It affects the transfer of loads from bearing3 and further dow the tower.

!	global%version='HAWC2MB 5.4'!	21.03.2007	TJUL/ANMH	Eigenfrequency analysis feature added. Performs analysis on every individual body
!		!	TJUL	Some pointer nullify's are changed to deallocate(pointer).
!	global%version='HAWC2MB 5.4'!	21.03.2007	TJUL/ANMH	Eigenfrequency analysis feature added. Performs analysis on every individual body
!		!	TJUL	Some pointer nullify's are changed to deallocate(pointer).
!	global%version='HAWC2MB 5.5'!	29.03.2007	TJUL	Small change in constraint bearing2 action input. Now only 4 parameters nessecairy as was allways the idea.
!	global%version='HAWC2MB 5.6'!	10.04.2007	TJUL	Bug fix related to number of output sensors in DLL output
!		!	ANMH	Change in external force module force_dll.f90. Update sequence of affected body changed.
!		!	TJUL	body_update_T is called in the end of post_init in order to allow for added stiffness, damping etc. by the rest of the initialization subroutines.
!	global%version='HAWC2MB 5.7'!	16.04.2007	TJUL	Small update of continue on no convergence
!	global%version='HAWC2MB 5.8'!	18.04.2007	TJUL	Mann turbulence files is closed after every buffer read. To allow several simulations acces to the same turbulence files.
!				New initial buffer read so out of x-bounds errors are avoided. Uses periodicity of turbulence boxes. In principal this allows for infinitely large simulations.
!	global%version='HAWC2MB 5.9'!	23.04.2007	TJUL	Opening of mann turbulence boxed with loops and waits so several simulations can acces the same turbulence.
		! 26.04.2007	TJUL	Only option in mbody output, wind output, hydro output
				SO dynamic stall input parameters put in as default. No need for parameter input if not changed.
		! 23.05.2007	TJUL	Check that turbulence scale_time_start is less the total simulation length
!				Correction of bug related to "only" option for output for main_body, wind and hydro output commands
	global%version='HAWC2MB 6.0'!	01.06.2007	TJUL	New error check that animation can be written to. Error message if not.
		! 08.06.2007	TJUL	New possibility of continuing read in masterfile in a new file with the command:'continue_in_file'. Infinite number of level can be made. Filename also written to logfile when line number is written.
		! 15.06.2007	TJUL	Logfile_name command option in simulation_input. Enables file written logfiles. Error messages more clear with *** ERROR *** as key word
		! 08.08.2007	TJUL	Aerodynamic drag forces on structures enables with the new module aerodrag.
!	global%version='HAWC2MB 6.1'!	03.09.2007	TJUL	Corrections made in continue_in_file option. End of file check removed - replaced with exit command.
		! 03.09.2007	ANMH	New unitnumber used when turbulence files are reopened. To avoid unit mismatch especiall
		! 05.09.2007	TJUL	Bug fixed in hydroload module. Only important when more than one hydro element are used.
		! 06.09.2007	TJUL	Bug fixed in hydroload module. Important if hydroelements have different coo than global.
		! 07.09.2007	TJUL	Bug fixed in hydroload module. Important if relative z_distances has been used as hydro element input
	global%version='HAWC2MB 6.2'!	20.09.2007	PBJA/TJUL	Dynamic stall module that combines the mhh Beddoes stall model with the MACflap model. Coded by PBJA, implemented by TJUL.
	global%version='HAWC2MB 6.3'!	10.10.2007	TJUL	New general output command "general stairs" for a series of step functions.
	global%version='HAWC2MB 6.4'!	29.10.2007	TJUL	Some files synchronized with HAWC2aero regarding !IFDEF compiler directives
		! 12.11.2007	TJUL	Torque and power output sensor in aero module modified to give correct results also with use of hub extenders
		! 27.11.2007	TJUL	Wake meandering model implemented, rearrangement of aero files to avoid compiler linker (circulation) errors

	! 29.11.2007	ANMH	Eigenvalue solver for complete turbine at standstill, initialisation of aerodrag element number!
!	global%version='HAWC2MB 6.5'! 04.01.2008	TJUL	User defined turbulence scaling implemented. Similar in principle to user defined shear.
	! 17.01.2008	TJUL	Bearing3 omegaS action command implemented to enable rotor speed control directly from external DLL
	! 04.02.2008	ANMH	Bouyancy forces calculated based on external pressures
	!	TJUL	Prestress constraint fix4
	!		DLL call to external wake kinematics dll changed. E.g. dynamic pressure added
!	global%version='HAWC2MB 6.6'! 04.02.2008	TJUL	bearing4. Cardan shaft constraint. Locked in relative translation. Locked in rotation around one vector
	! 08.02.2008	TJUL	Bug fixed in turbulence module affecting version 5.5.
	! 08.02.2008	TJUL	Bug fixed regarding turbulence scaling factors. In version 6.5 the turbulence was excluded for normal use - corrected.
	! 08.02.2008	TJUL	Previous .dat file deleted when hawc_binary output files are written.
	! 11.02.2008	TJUL	In mann and flex turbulence module: std scaling factors default to v=0.8 u=1.0 w=0.5
	! 11.02.2008	TJUL	Bug fixed regarding IEC-gust EWS
	! 13.02.2008	TJUL	New Auto distribution of hydrodynamic calculation points possible
	! 13.02.2008	TJUL/ANMH	Bug fixed regarding hydrodynamic boyancy. Axial force on conical members changed from distributed forces to constant force contributions instead (to decrease sensitivity to number of hydro points)
	!		F function only on external kinematics in hydro module.
	!		Dynamic pressure contribution include. Also in wkin_dll calling format.
	!		Coordinates in wkin_dll call changed from global to local hydro coo (origo in 0,0,MSL Z-dir vertical upwards, X-dir in wave direction)
	!		Change in hydro output command "fm" and "fd"
	! 15.02.2008	TJUL	trim commands inserted in reading of master input "begin" and "exit" commands.
	! 15.02.2008	TJUL	Bug fixed regarding output of "free_wind_hor" command.
	! 19.02.2008	TJUL	S.O. dynamic stall parameters included as default
!	global%version='HAWC2MB 6.7'! 26.02.2008	TJUL	Bug fixed regarding mbdy action command with "local" coordinates
	! 27.02.2008	TJUL	Extra error messages for errors during aero read routines
	! 29.02.2008	TJUL	Small modifications in eigenvalue solver so large eigenvalue problem can be solved without very large stack size
	! 06.03.2008	TJUL	Dynamic pressure on conical sections also in hydroload
	! 09.03.2008	TJUL	Wordlength increased to 100 chars in general input reading.
	! 11.03.2008	TJUL	Error handling for infinity cases in hawc_binary output
	! 11.03.2008	ANMH/TJUL	Dynamic pressure on conical hydro sections
	! 11.03.2008	TJUL	Update of mann turb reading routines for boxes where N_y<>N_z
	! 11.03.2008	TJUL	Small modifications in the wake module for robustness
	! 13.03.2008	TJUL	Update of mann turb reading so buffer is updated also when requested point is before buffer start pos (especially important for wake sim. with several wake sources)
!	global%version='HAWC2MB 6.8'! 14.03.2008	TJUL	Update of tower shadow pot2 and jet2 models, so they can handle multiple sources.
!	global%version='HAWC2MB 6.9'! 21.03.2008	TJUL	Increase of maxloops in mann turbulence reading.
	global%version='HAWC2MB 7.0'! 09.04.2008	TJUL	New check in license_manager
!	global%version='HAWC2MB 7.1'! 21.05.2008	TJUL	Bug fixed in command line interpreter (if too many command words were present)
	! 26.05.2008	ANMH/TJUL	Concentrated masses option in main_body (no coriolis effects etc. so far)
	! 11.06.2008	TJUL	Extra acceleration sensor including gravity
	! 13.06.2008	TJUL	Minimum values of rotational speed and free wind speed in the induction module.
!	global%version='HAWC2MB 7.2'! 15.06.2008	TJUL	F startup function and relative motion in aerodrag included

!	global%version='HAWC2MB 7.3'!	22.07.2008	TJUL		extra check on shear power law expression in wind module to avoid NAN's
		!	01.08.2008	TJUL	Concentrated mass in modal calculation
					Bug in calculation procedure of aerodynamic torque and power corrected.
					Bug in tower shadow pot2 and jet2 models corrected. Important only if
					rotation of tower legs were present.
!	global%version='HAWC2MB 7.4'!	05.08.2008	ANMH		Change in output of forces/moments in general. More correct when long
					elements are used.
					Distributed external loads, inertial loads included on top of elastic
					part. Previously only elastic part used.
				ANMH	Hydrodynamic axial drag possible
					Bearing 2 updated to allow for +-180deg rotation
				TJUL/HAMA	Update of tower shadow 2 models. Factors multiplied instead of
					deficits added. Better when several tower shadow sources are used.
	global%version='HAWC2MB 7.5'!	08.08.2008	TJUL		Correction of matrix conditioning during eigenvalue calculations.
					Version 7.3 and 7.4 was not correct regarding this!
!	global%version='HAWC2MB 7.6'!	24.09.2008	TJUL		Bug fixed in tower pot2 model.
		!			Old LIB files for old HAWC input format read, removed from project
	global%version='HAWC2MB 7.7'!	01.10.2008	TJUL		Extra logfile output regarding load linking.
		!			NEED EXTRA ATTENTION -NOT COMPLETELY FIXED YET- WORK ONLY when body
					structure is defined along the body z coordinates!
					Bug fixed in aerodrag module (important if aerodrag is linked to a
					structure where local element and body coo doesn't coincide)
				PBJA/TJUL	Mann turbulence generator DLL call added
				TJUL	Warning written if a comma "," is written within a command line
	global%version='HAWC2MB 7.8'			TJUL	Animation files for structure eigenvalues calc placed in same directory
					as eigenvalue list
				TJUL	Limitations in orientation_relative removed. Any coupling node can now
					be chosen. Eigenvalue solver however not updated for this option yet.
	global%version='HAWC2MB 7.9'!	17.11.2008	TJUL		Extra subroutines in normal DLL hawc_dll call. Subroutines added: init
					and message.
				TJUL	Directories needed are now automatically created if they do not exist
				TJUL	A status sensor is added in the general outputs.
				TJUL	Solvertype is default set to 1=newmark
				TJUL	In dynamic wake model, downstream distance without offset, makes better
					agreement with measurements and FIDAP
				TJUL	In Dynamic Wake Model: Possibility of writing file with Ct and Cq data
				TJUL	Change in force DLL module. Now bodyname refers to a main_body
				ANMH	Update of initial hydrodynamic loads for added mass/stiffness
					calculation
				ANMH	Update of loadlinker and solver wrt. calculation of added
					mass/stiffness/damping.
					Asymmetric solver implemented - to improved convergence for hydrodyn.
					problems(not active in version 7.9)
	global%version='HAWC2MB 8.0'!	28.11.2008	TJUL		In wake meander model. User calculated deficits can be read.
				TJUL	Change in error message of tower shadow jet and jet2 model - when
					points requested is inside tower.
				TJUL	General output sensor "status" is set to -1 in last time step.
				PBJA	Near wake induction model implemented
				PBJA	Possibility of exporting wind field including shear, tower shadow, wake
					etc.
				PBJA	In normal induction model. First order time filter on induced
					velocities replaced with two indicial functions - modified filter
					approach. Better agreement with NASA AIMEs experiment.
				ANMH/TJUL	Bug correction of concentrated mass indexing in eigenvalue calculation.
					Important (only) if mass is connected to body node 1
				ANMH/TJUL	Possibility of calculating structural natural frequencies without
					damping contribution. More robust calculation

	global%version='HAWC2MB 8.1'!	09.01.2009	TJUL	In mann model. Auto generation of missing turbulence in more general form.
		! 09.01.2009	TJUL	In hydro module. Currents included, wave direction included.
		! 16.01.2009	ANMH	Assymmetric solver option, which decreases number of iterations for offshore simulations considerable. Newmark-symmetric option
!	global%version='HAWC2MB 8.2'!	20.01.2009	TJUL	Bug found in version 8.0 regarding Dynamic wake meander model. Input deficits to Aislie model with wrong value in last radius point.
	global%version='HAWC2MB 8.3'!	21.01.2009	TJUL	Rearrangement of write procedure for final deficit in Dynamic wake meander model. Array-out-of-bound could occur in special cases
		! 02.02.2009	TJUL	New twist angle sensor in output_at aero commands
		! 27.02.2009	TJUL	Small correction of tip loss model. sin(phi) instead of phi.
		! 11.03.2009	ANMH/TJUL	Update of modal solver. Now also usable for floating systems.
		! 18.03.2009	HAMA/TJUL	Update of Dynamic wake meander model. Deficit are now more narrow than previous. Default parameters k1,k2 are changed.
		! 05.05.2009	ANMH	Bug fix in mass matrix and orthogonality of local orientation matrices. Important (only) with prebend and mass center offset from elastic axis.
		! 05.05.2009	TJUL	Small updates regarding mbdy commands instead/supplementary to old body commands in new_htc_structure inputs
		! 05.05.2009	ANMH	Extra parameter in hydro element regarding linear axial drag contribution.
		! 06.05.2009	TJUL	More residual information outputted in case of no convergence
!	global%version='HAWC2MB 8.4'!	11.05.2009	TJUL	New input check on number of mann box points. power of 2 criteria.
!		! 12.05.2009	ANMH	Mode shape animation files written in appropriate directories.
		! 13.05.2009	TJUL	Initialization of timosection properties No double eigenvalue sets are written in table of structural frequencies
!	global%version='HAWC2MB 8.5'!	14.05.2009	ANMH	Bug corrected in eigenvalue solver related to version 8.3 and 8.4
!	global%version='HAWC2MB 8.6'!	08.07.2009	TJUL	Bug fix related to mann turbulence look-up indexes for points just outside the turbulence box.
		! 08.07.2009	TJUL	New updates of DWM wake model. New ainslie-15.exe and modification of default parameters.
	global%version='HAWC2MB 8.7'!	24.08.2009	TJUL	In main_body input limitation of 4 c2def points lower to 2. If less than 4 points, linear interpolation is used.
		! 30.08.2009	TJUL	Element coordinates can now be used without limitations. Local coordinate system written in beam_output_file.
		! 04.09.2009	ANMH	Loadlinker updated so arbitrary body coordinations systems can be used. Linker now follows local curved beam direction
		! 04.09.2009	TJUL	Positive definite damping model originally formulated by Morten H. Hansen is included in HAWC2. Makes it possible to utilize the shear center position away from the elastic axis without problems with damping model.
		! 05.09.2009	TJUL	Small bugfix related to aerodrag module.
!	global%version='HAWC2MB 8.8'!	08.10.2009	TJUL	Bug related to damping model changes in version 8.7 corrected.
!	global%version='HAWC2MB 8.9'!	09.10.2009	ANMH/TJUL	New structure output: Structure_inertia_file_name
	global%version='HAWC2MB 9.0'!	26.11.2009	TJUL	New check for input errors regarding negative diameters in aerodrag module
		! 03.12.2009	TJUL	In wake model. Ainslie-15.exe replaced by ainslie-15.dll, to enable execution on linux platforms using WINE
		! 21.12.2009	TJUL	In wake model. Bug fixed dealing with several neighbouring wind turbines. Change in turbine order for ainslie15.dll input/output
		! 30.12.2009	TJUL	Flex integer format option in output.
		! 04.01.2010	TJUL	Change in variables in eigenvalue module to avoid stack errors
		! 05.01.2010	TJUL	Change in loadlinker merge criteria to avoid error with closely spaced nodes
		! 31.01.2010	TJUL	New control DLL module names type2_dll
		! 31.01.2010	TJUL	Possibility to input case_sensitive words using ' symbols. Especially related to control subroutine names.

	! 15.02.2010	TJUL	Change in wind shear logarithmic format to ensure a shear of zero below global zero.
global%version='HAWC2MB 9.1'!	29.03.2010	TJUL	New parameter possible in mbdy moment_int actions command
	! 31.03.2010	ANMH	Possibility of external systems solved together with HAWC2, this goes for bodies and constraints
	! 01.04.2010	TJUL	Small update of result file sensorlist output for hawc_ascii and hawc_binary
	! 15.04.2010	TJUL	Updates in FORCE DLL module. New initialization option, label option.
	! 17.05.2010	TJUL	Update of wind ramps to speed up simulation time
	! 29.06.2010	TJUL	DLL module, type2_dll updated regarding first outputs in dll calls
	! 16.07.2010	TJUL	Small change in compiler settings.
global%version='HAWC2MB 9.2'!	13.08.2010	TJUL	Possibility for aerodynamic sections positioned according to ae_file input.
	! 25.08.2010	TJUL	Updated procedure for hub coo which defines coo with arbitrary rotor orientation
	! 09.09.2010	TJUL	Simulation stop enabled by external dll action.
	! 13.09.2010	JOMH	Updated eigenvalue solution procedure
	! 13.09.2010	JOMH	Zero-termination of all strings used for dll's
	! 28.09.2010	TJUL	Bug correction from version 9.1 regarding wind steps.
! global%version='HAWC2MB 9.3w'	! 06.10.2010	TJUL	Bug correction in interpolation of profile coef when several pc sets are used.
	! 20.10.2010	TJUL	Bug correction of predictor in newmark solver. Version 9.0 and 9.1 gave problems coupling in controllers
	! 21.10.2010	TJUL	Eigenvalue solver from version 9.2 removed and old 9.1 version included instead. Not correct solutions in all cases.
	! 21.10.2010	TJUL	Turbulence buffer not updated when buffer contains the full turbulence box.
! global%version='HAWC2MB 9.4'!	21.10.2010	TJUL	Code updated for handling multiple aerodynamic rotors
	! 26.10.2010	TJUL	Be aware that the near wake induction model is not working in this edition. The normal induction model works fine though.
	! 26.10.2010	JOMH	Eigenvalue solver updated again, so now it should be both correct and robust
! global%version='HAWC2MB 9.5'!	12.11.2010	TJUL	Bug fixed when outputting wake pos when no wake defined - code crash occurred.
	! 17.11.2010	TJUL	BEM rewritten in more structured way and to make sure local properties in grid points are all local. More correct for non-uniform loading
	! 19.11.2010	TJUL	IN BEM, time filters are now on induced velocities instead of factors, same goes with azimuthal yaw correction in induction.
	! 21.11.2010	TJUL	WSP lookup only performed for first iteration to save simulation time.
	! 24.11.2010	TJUL	Final adjustments of BEM induction
! global%version='HAWC2MB 9.6'!	27.11.2010	TJUL	Improvements of yaw correction in BEM calculation, comparison with FIDAP
	! 02.12.2010	TJUL	Bugfix related to output of DWM wake position
! global%version='HAWC2MB 9.7'!	03.12.2010	TJUL	Improvements of yaw correction in BEM calculation, comparison with FIDAP
	! 03.12.2010	TJUL	BEM restructured for more correct local CT prediction, time constants on induced velocities, yaw correction on induced axial velocities instead of factors
	! 03.12.2010	TJUL	BEM improved regarding aerodynamic yaw correction, compared with actuatordisc results
	! 03.12.2010	TJUL	BEM improved regarding dynamic time constants, compared with actuatordisc results
	! 03.12.2010	TJUL	Dyn. time constants reduced for first 10seconds to reduce time for initial equilibrium
! global%version='HAWC2MB 9.8'!	17.12.2010	TJUL	Small bug correction. Crash occurred when aero output requested when rotor was not defined
	! 28.12.2010	MHHA	Bug fix regarding omega vector for aero module. Version9-2 to 9.7 had

!	global%version='HAWC2MB 9.9'	! 05.01.2011	TJUL	problems with rotor orientations azimuthally angle more than +90deg. Update regarding wake meandering, lowpass filter in time instead of area based filter
!	global%version='HAWC2MB 10.0'	! 17.01.2011	TJUL	New calibration in DWM model. Ainslie_16.dll used.
!	global%version='HAWC2MB 10.1'	! 01.02.2011	TJUL	BEM bug correction regarding induction for two bladed turbines. + DWM model deficit k1 parameter changed to 0.20 as default
!	global%version='HAWC2MB 10.2'	! 01.02.2011	TJUL	User defined a-ct relation in BEM included
!	global%version='HAWC2MB 10.3'	! 08.02.2011	TJUL	DLL action command aero bem_grid_a inserted.
!	global%version='HAWC2MB 10.4'	! 18.03.2011	TJUL	In DWM model, k1 parameter default value changed back to 0.13 (good match with Egmond aa Zee measurements)
		! 13.05.2011	TJUL/LEOB	Bug corrections in the maghmmh dynstall model
		! 16.05.2011	ANMH	Update and general improvement of hydrodynamic mass so is it coded in body coordinates (time varying)
!	global%version='HAWC2MB 10.5'	! 17.05.2011	TJUL	Small updates of modal_new.f90 to minimize stack usage
		! 17.05.2011	ANMH	Concentrated hydrodynamic added masses also included in new procedure, which makes the solver converge faster and more stable than previous
!	global%version='HAWC2MB 10.6'	! 15.06.2011	TJUL	Update of mbody state_rot output
		! 12.08.2011	TJUL	Small update in variable check to fulfill requirements from new compiler
		! 30.08.2011	TJUL	Updates in hydrodynamics related to flooded members.
		! 31.08.2011	HAMA/TJUL	Limitation in tangential induction changed (tangential induction was not correct for high loading Ct)
		! 31.08.2011	LEOB	New updated model for dynamic stall of trailing edge flaps
		! 05.09.2011	TJUL	Updates in buoyancy regarding point change in diameters
		! 05.09.2011	TJUL	Update in structure output. Hydro added mass outputted if defined.
		! 13.09.2011	LEOB	New alfadot sensor in aero output
		! 19.09.2011	TJUL	Hydro added mass solver module updated for inner flooded area
		! 26.09.2011	KNKR	New spinner output sensor in aeroload module
!	global%version='HAWC2MB 10.7'	! 04.10.2011	TJUL	External forces enabled for external modules
		! 18.10.2011	TJUL	In DWM model, Multiple wakes handled by choosing the deficit with largest wsp reduction. Previously a summation of deficits was performed
		! 24.10.2011	TJUL	In buoyancy part. Correction with eps at mudlevel, to improve stability when structure ends at mudlevel.
	global%version='HAWC2MB 10.8'	! 02.11.2011	TJUL	Fourrier based low pass filter in DWM model instead of second order filter
		! 09.11.2011	LEOB/TJUL	Update in dynamic induction to include the influence of trailing edge flaps
		! 18.11.2011	TJUL	New random output sensor added to general output commands.
		! 22.11.2011	ANMH/TJUL	Update in topology initial rotation velocities. Should decrease initial transients
		! 22.11.2011	TJUL	Aerodynamic load is removed for first 5 second and then gradually put on structure (fully applied at 10s) to avoid convergence problems during initial transients.
		! 05.12.2011	TJUL	Close dll's inserted to increase robustness on especially windows 7 platforms
		! 05.12.2011	ANMH	Eigenvalue solver update to account for non-coinciding nodes and free relative rotation
		! 02.11.2011	ANMH	Orientation of node in call to FORCE_DLL is changed (back) to global reference
		! 02.11.2011	ANMH	Disabling of constraints can now be handled - new command "disable_at" is introduced for constraints FIX0, FIX1, BEARING1 and BEARING2
		! 02.11.2011	ANMH	"INPUT" subroutine introduced in EXTSYS which enables HAWCDLL to send output to EXTSYS
		! 06.11.2011	LEOB	Update of dynamic stall models MHH and ATEF for correct handling of +pi angle of attack crossing.
		! 07.11.2011	TJUL	New aero command 'output_profile_coef_filename', enables output of static interpolated profile coefficients

	! 07.11.2011	ANMH/TJUL	Update of initial structural velocity conditions, to reduce the initial transients in general
	! 08.11.2011	TJUL	New aero sensor, where is is possible to ouput the local elastic torsion
global%version='HAWC2MB 10.9'	! 15.12.2011	TJUL	New procedure for calculating non-rotating hub coordinate system. important for free-yawing rotors.
global%version='HAWC2MB 11.0'	! 21.12.2011	TJUL	New dll action commands (wind windspeed_u, wind winddir)
	! 21.12.2011	TJUL	For DWM wake model, Ainslie_17.dll replaces Ainslie_16.dll. Updated regarding number of neighbor turbines in the flow solver.
	! 30.01.2012	TJUL	Bug fix related to input of using different aerodynamic_ae sets.
	! 13.01.2012	TJUL	Bug fix related to naming of 'output_profile_coef_filename' in the aero block
	! 13.01.2012	LEOB	Update of deflection shape integrals in ATEF dyn. stall model. Based on UPWIND test cases.
	! 21.03.2012	TJUL	Update in DWM wake model. Turbulence intensity for kinematic viscosity is now from ambient tint and not meander turb tint.
	! 23.03.2012	TJUL	New sensor mbdy state_at2, where the xy offset is defined in local c2def coordinates instead of elastic axis coo.
global%version='HAWC2MB 11.1'	! 21.12.2011	TJUL	New dll action commands (wind windspeed_u, wind winddir)
	! 24.04.2012	TJUL	Bug fix in IEC gust EWS. Wrong rotor diameter used in normalization - manual updated too.
global%version='HAWC2MB 11.2'	! 09.05.2012	TJUL	Bug fix related to aerodynamic induction of one-bladed turbines.
global%version='HAWC2MB 11.3'	! 24.05.2012	TJUL	In tower shadow JET model, distance criteria changed to match physical units. Only of importance if tower radius < 1m
	! 25.05.2012	TJUL	Bug fix in tower shadow JET model. x-offset normalized with tower diameter instead of radius.
	! 10.07.2012	TJUL	Bug fix in S.O. dyn. stall model
	! 10.07.2012	ANMH	External output sensors in ESYS (external systems) enabled
	! 10.07.2012	ANMH	In hydro dynamics. Added mass and drag defined in two dimensions for new general hydro section
	! 10.07.2012	ANMH	DLL call for ESYS (external systems) changed to MEFF,CEFF,KEFF instead of newmark matrices
	! 10.07.2012	ANMH	Bug fix in output of mass centers
	! 10.07.2012	ANMH	Eigenvectors output together with eigenfrequencies for local bodies
	! 20.07.2012	TJUL	New wind sensor "wind free_wind_shadow" including effects of tower shadow
global%version='HAWC2MB 11.4'	! 20.07.2012	TJUL/HAMA	Induction model for VAWTC's implemented.
	! 15.08.2012	LEOB/TJUL/GEORG	Update of induction model for high CT loading
	! 11.09.2012	TJUL	New aero output sensor "aero grid_all_induc_u"
	! 27.09.2012	ANMH/TJUL	In hawc ascii outout, limit of 500 channels removed
	! 27.11.2012	TJUL	Correction of bug regarding more_ae data sets than 2.
global%version='HAWC2MB 11.5'	! 06.12.2012	TJUL	in orientation relative, new "relpos" command enabled
	! 10.12.2012	TJUL	Taylors hypothesis included in EOG gust
	! 21.03.2013	GEPIR	Speedup optimization modification of aeroload_induction_bem module
	! 22.03.2013	TJUL	New general output impulse function added
	! 22.04.2013	TJUL	Mann turbulence DLL is closed after turb generation, to remove fault seen on linux clusters with multiple turbulence set created
	! 03.05.2013	TJUL	New Flex int writing loop to minimize writing time on network drives
	! 14.05.2013	TJUL	Wave direction reversed to match manual definition
	! 26.06.2013	TJUL	Bug fix in VAWT module regarding aerodynamics on turbines with more blades than 2
	! 27.06.2013	TJUL	Reordering of output related to command "body_eigenanalysis_file_name". Frequencies first, later eigenvectors.
! global%version='HAWC2MB 11.6'	! 25.09.2013	TJUL	VAWT update for handling non vertical blade configs

	!	30.09.2013	MACG	Update of MHHA dyn. stall model to account for extra term important for VAWT operation
	!	30.09.2013	TJUL	In aero output. "tors_e" options inserted parallel to "tors_ang" to match explanation in the manual
	!	01.10.2013	TJUL	Bug fix in aero drag, sign issue on force direction for negative force directions.
	!	11.10.2013	TJUL	With VAWT's aero center is moved to C <sub>1/2</sub> instead of C <sub>3/4</sub>
	!	03.01.2014	TJUL	Encrypted blade data
	!	04.01.2014	TJUL	Move of update time call to external water kinematics dll. To ensure it is also called even if no hydro elements are used.
	!	16.01.2014	TJUL	Aero output parameters ct_local, cq_local and tiploss_f enabled
	!	17.01.2014	TJUL	Aero BEM induction. Small change in procedure of how to find induction grid loading. Now in line with VAWT approach.
	!	27.02.2014	TJUL	Change in shears, so size of shears change if windsteps are included.
	!	06.03.2014	EBRA	General prepare for intel compiler
	!	13.03.2014	TJUL	new aero option: 3D profile correction using Snel's approach
	!	19.03.2014	LARH	New stiffness proportional damping model
	!	19.03.2014	ANMH	New eigenvalue option including contributions from external systems
	!	19.03.2014	ANMH	Super element approach to condensate degrees of freedom for sub systems - eg jackets. Still not a perfect match with full DOF solution for internal cross sectional members of a static underdetermined structure!
	!	20.03.2014	TJUL	Turbulence export option re-implemented
	!	14.05.2014	TJUL	Encrypted password lib updated
	!	14.05.2014	TJUL	Procedure to ensure more robust auto shut-off of bem for idling/standstill conditions
global%version='HAWC2MB 11.7'	!	21.05.2014	TJUL	Added stiffness contribution from version 11.6 is switched off again - caused increase in iterations especially for jackets
global%version='HAWC2MB 11.8'	!	16.07.2014	TJUL	Memory use related to output sensors minimized
	!	22.07.2014	TJUL	Create directory function increased for "../.." paths
	!	22.07.2014	TJUL/ANYD/MMPE	Dyn stall MHH model rolled back to version 11.5. The modification in 11.6 wrt. VAWT affected HAWT operation. A better dyn stall model for VAWT must be coded
global%version='HAWC2MB 11.9'	!	22.07.2014	TJUL/ANYD/MMPE	Comprehensive testprogram established. Used on this version and future.
	!		TJUL	Read and write status declared when working with files. Should prevent access errors on net work drives especially
	!		TJUL	Stop code defined when code is stopped by internal criteria
	!	12.09.2014	TJUL	In BEM model with "use_mean_average" switched on, the inducted velocities are now found based on a consistent use of average wind speed in annular element.
	!	19.09.2014	TJUL	Update to BEM "use_mean_average" stuff from 12.09.2014. The local grid velocities was still present a few places
	!	22.10.2014	TJUL/ANMH	Code sync with svn version. Prepared for intel compilation.
	!	23.10.2014	ANMH	Contributions from inertial/gyroscopic effect of concentrated masses added in a general way. It is now OK to use concentrated massed on the rotor part.
!	!	03.09.2014	TJUL	Bug fix, userdefined number of azimuthal stations was not active. Default value of 16 stations were always present until now.
	!	13.11.2014	GEORG	Bugfix in BEM module, relevant when negative windspeeds occurs
	!	08.12.2014	TJUL	Update in SNEL 3D profile correction method
	!	16.12.2014	GEORG	Bugfix of mhh dyn stall model wrt rel velocity
	!	16.01.2014	TJUL/MHHA/ANMH	Bugfix wrt position of rotor center in aero variables
	!	10.02.2015	MMPE	Small update in call of output function (if aerodyn rotor not defined)
	!	20.02.2015	TJUL	Update in BEM "use_mean_average" approach + approach to find load in local BEM grid
!	!	17.03.2015	TJUL	Option to specify dyn stall model manually in the _ae file depending on radial location.
	!	27.10.2014	CPAV	TKIM anisotropic beam element added. CPAV damping introduced (the damping matrix is the same than MHH, but it's generalized to support 6x6 stiffness

	! 20.03.2015	TJUL	matrix) in wind speed module. factor used for ramps etc is also applied on wake deficits and turbulence to prevent negative wind speed in simulation start up.
	! 20.03.2015	TJUL	Update in output file write updated in order to allow more than 999 sensors
	! 25.03.2015	TJUL	Bugfix relatede to _ae dyn stall choice from 17.03.2015
	! 30.04.2015	TJUL	Type2_dll. New option to include "initstring" and "message"
	! 05.05.2015	TJUL	New option in DWM method (multiple_deficit_method) - summation or max deficit operator
	! 27.05.2015	TJUL	Update in Mann turbulence dll call. Now the mann_win32.dll and ressource_win32.dll must be present in same folder as HAWC2
	! 28.05.2015	TJUL	This version is compiled with intel visual fortran
global%version='HAWC2MB 12.2'	! 09.07.2015	TJUL	Additional read specification when opening files. To avoid network multiple access errors
	! 21.07.2015	ALSTA	Compiler flags needed for HAWCStab2 compilation inserted.
	! 24.07.2015	TJUL	Update in create directories procedure - needed for special situations where the intel version was blocked from creating certain directories.
	! 24.07.2015	TJUL	Mann turbulence generator call moved from mann module directly. No need for the mann.dll or mann_win32.dll anymore

## Coordinate systems

The global coordinate system is located with the z-axis pointing vertical downwards. The x and y axes are horizontal to the side.

When wind is submitted, the default direction is along the global y-axis. Within the wind system meteorological u,v,w coordinates are used, where u is the mean wind speed direction, v is horizontal and w vertical upwards. When x,y,z notation is used within the wind coo. this refers directly to the u,v,w definition.

Every substructure and body (normally the same) is equipped with its own coordinate system with origo in node1 of this structure. The structure can be arbitrarily defined regarding orientation within this coordinate system. Within a body a number of structural elements are present. The orientation of coordinate systems for these elements are chosen automatically by the program. The local z axis is from node 1 to 2 on the element.

The coordinate system for the blade structures must be defined with the z axis pointing from the blade root and outwards, x axis in the tangential direction of rotation and y axis from the pressure side towards the suction side of the blade profiles. This is in order to make the linkage between aerodynamics and structure function.

In order to make a quick check of the layout of the structure the small program "animation.exe" can be used (this requires that an animation file has been written using the command animation in the Simulation block). The view option in this program is handled by keyboard hotekeys:

### **Animation Hotkeys:**

translate: (shift)+{x,y,z}

rotate: arrow keys

rotate about line-of-sight: ctrl+left/right

zoom in: ctrl+up

zoom out: ctrl+down

amplify displacement (only usefull for animation of natural frequencies): +

decrease displacement (only usefull for animation of natural frequencies): -

If the animation does not start, press "s"

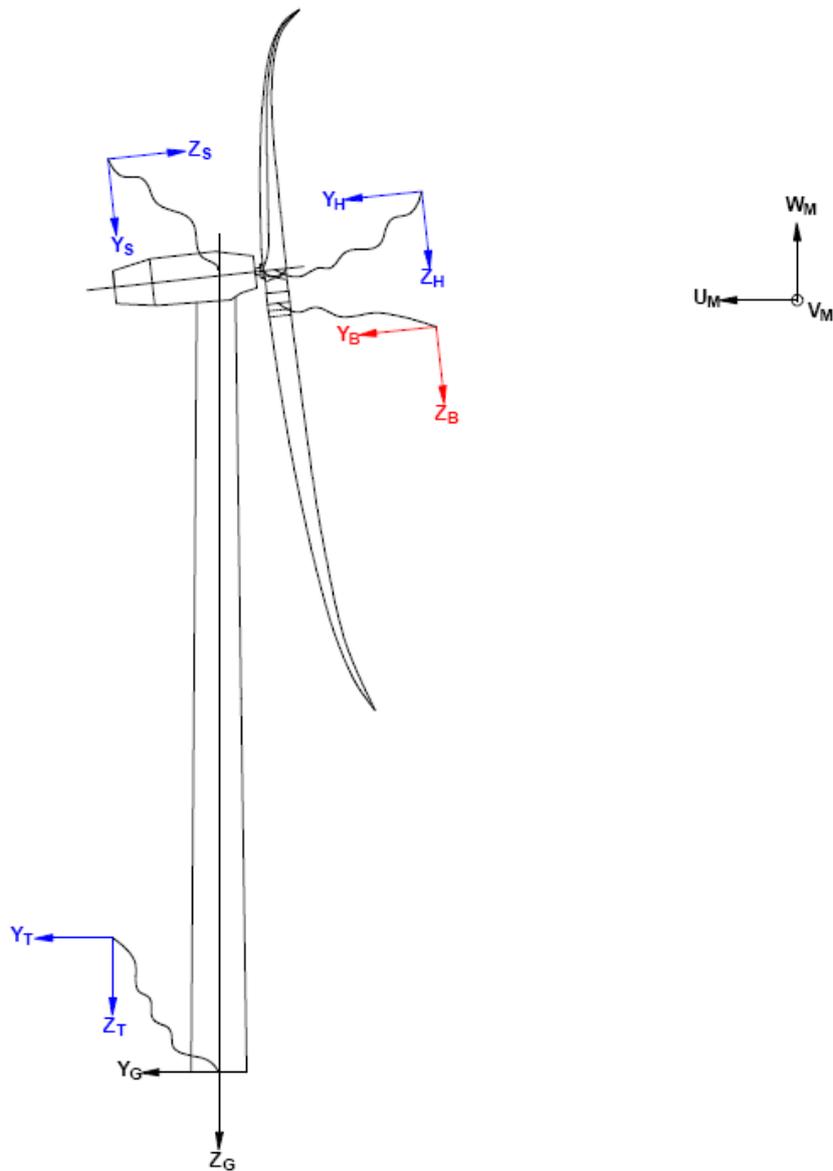


Figure 1. Illustration of coordinate system as result of user input from example in section Example of main input file at page 107. There are two coordinate systems in **black** which are the default coordinate systems of global reference and default wind direction. The **blue** coordinate systems are main body coordinate systems attached to node 1 of the substructure, the orientation of these are fully determined by the user. The **red** coordinate systems are also defined by the user, but in order to make the linkage between aerodynamic forces and structure work these have to have the  $z$  from root to tip,  $x$  in chordwise direction and  $y$  towards the suction side.

# Simulation

## Main command block - Simulation

This block shall be present when time simulations are requested – always.

Obl.	Command name	Explanation
*	time_stop	1. Simulation length [s]
	solvertype	1. Choice of available solver method (1=newmark)
	solver_relax	1. Relaxation parameter on increment within a timestep. Can be used to make difficult simulation run through solver when parameter is decreased, however on the cost of simulation speed. Default=1.0
	on_no_convergence	Parameter that informs solver of what to do if convergence is not obtained in a time step. 1. 'stop': simulation stops – default. 'continue': simulation continues, error message is written.
	convergence_limits	Convergence limits that must be obtained at every time step. 1. epsresq, residual on internal-external forces, default=10.0 2. epsresd, residual on increment, default=1.0 3. epsresg, residual on constraint equations, default=1E-7
	max_iterations	1. Number of maximum iterations within a time step.
	animation	Included if animation file is requested 1. Animation file name incl. relative path. E.g. ./animation/animation1.dat
	logfile	Included if a logfile is requested internally from the htc command file. 1. Logfile name incl. relative path. E.g. ./logfiles/log1.txt

## Sub command block – newmark

This block shall be present when the solvertype is set to the newmark method.

Obl.	Command name	Explanation
	beta	1. beta value (default=0.27)
	gamma	1. gamma value (default=0.51)
*	deltat	1. time increment [s]
	symmetry	1. Solver assumption regarding mass, damping and stiffness matrices (1=symmetric (default), 2=assymmetric (recommended for offshore structures). When hydrodynamic loading is applied this parameter will automatically change to 2.)

## Structural input

### Main command block – new\_htc\_structure

Obl.	Command name	Explanation
	beam_output_file_name	1. Filename incl. relative path to file where the beam data are listed (output) (example ./info/beam.dat)
	body_output_file_name	1. Filename incl. relative path to file where the body data are listed (output) (example ./info/body.dat)
	struct_inertia_output_file_name	1. Filename incl. relative path to file where the global inertia information data are listed (output) (example ./info/inertia.dat)
	body_eigenanalysis_file_name	1. Filename incl. relative path to file where the results of an eigenanalysis are written. (output) (example ./info/eigenfreq.dat)
	constraint_output_file_name	1. Filename incl. relative path to file where the constraint data are listed (output). (example ./info/constraint.dat)
	structure_eigenanalysis_file_name	1. Filename incl. relative path to file where the results of a complete turbine eigenanalysis are listed (example ./info/eigen_all.dat). Animation files of the first modes are placed in same directory as the HAWC2 executable. 2. Optional parameter determining if structural damping is included in the eigenvalue calculation or not. (0=damping not included, most robust method, 1=damping included default)
	system_eigenanalysis	Eigenvalue calculation of the total system including external systems attached, eg. mooring lines. Constraint equations are also fully included in the analysis. 1. Filename incl. relative path to file where the results of a complete turbine eigenanalysis are listed (example ./info/eigen_all.dat). Animation files of the first modes are placed in same directory as the HAWC2 executable. 2. (optional) Parameter determining if structural damping is included in the eigenvalue calculation or not. (0=damping not included, most robust method, 1=damping included default) 3. (optional) Number of modes outputted. 4. (optional) Time for when the eigen analysis is carried out. Eg. after a settling of a floating system.

### Sub command block – main\_body

This block can be repeated as many times as needed. For every block a new body is added to the structure. A main body is a collection of normal bodies which are grouped together for bookkeeping purposes related to input output. When a main

body consist of several bodies the spacing the name of each body inherits the name of the master body and is given an additional name of ‘\_#’, where # is the body number. An example could be a main body called ‘blade1’ which consist of two bodies. These are then called ‘blade1\_1’ and blade1\_2’ internally in the code. The internal names are only important if (output) commands are used that refers to the specific body name and not the main body name.

From version 11.6 it is possible to attach an encrypted DLL where the blade data can be extracted. An example of how to encrypt this can be obtained by request through the [www.hawc2.dk](http://www.hawc2.dk) web page.

Obl.	Command name	Explanation
*	name	1. Main_body identification name (must be unique)
*	type	1. Element type used (options are: timoschenko)
*	nbodies	1. Number of bodies the main_body is divided into (especially used for blades when large deformation effects needs attention). Equal number of elements on each body, eventually extra elements are placed on the first body.
*	node_distribution	1. Distribution method of nodes and elements. Options are: <ul style="list-style-type: none"> <li>• “uniform” nnodes. Where uniform ensures equal element length and nnodes are the node numbers.</li> <li>• “c2_def”, which ensures a node a every station defined with the sub command block c2_def.</li> </ul>
	damping	Original damping model that can only be used when the shear center location equals the elastic center to ensure a positive definite damping matrix. It is recommended to use the <b>damping_posdef</b> command instead. Rayleigh damping parameters containing factors that are multiplied to the mass and stiffness matrix respectfully. ! Pay attention, the mass proportional damping is not contributing when a mbody consist of multiple bodies ! <ol style="list-style-type: none"> <li>1. <math>M_x</math></li> <li>2. <math>M_y</math></li> <li>3. <math>M_z</math></li> <li>4. <math>K_x</math></li> <li>5. <math>K_y</math></li> <li>6. <math>K_z</math></li> </ol> <p><b>NOTE:</b> This damping model cannot be used with the Fully Populated Matrix (“FPM 1”, see below) beam element!</p>
	damping_posdef	Rayleigh damping parameters containing factors. $M_x$ , $M_y$ , $M_z$ are constants multiplied on the mass matrix diagonal and inserted in the damping matrix. $K_x$ , $K_y$ , $K_z$ are factors multiplied on the moment of inertia $I_x$ , $I_y$ , $I_z$ in the stiffness matrix and inserted in the damping matrix. Parameters are in size approximately the same as the parameters used with the original damping model written above. ! Pay attention, the contribution from mass proportional damping is limited when a mbody consist of multiple bodies ! <ol style="list-style-type: none"> <li>1. <math>M_x</math></li> <li>2. <math>M_y</math></li> <li>3. <math>M_z</math></li> <li>4. <math>K_x</math></li> <li>5. <math>K_y</math></li> <li>6. <math>K_z</math></li> </ol> <p><b>NOTE:</b> This damping model cannot be used with the Fully</p>

Obl.	Command name	Explanation
		Populated Matrix (“FPM 1”, see below) beam element!
	damping_aniso	<p>Mixed mass/stiffness proportional and stiffness proportional damping parameters containing factors. <math>\eta^m_x</math>, <math>\eta^m_y</math>, <math>\eta^m_t</math> are constants multiplied on a mixed mass/stiffness matrix diagonal and inserted in the damping matrix. <math>\eta^s_x</math>, <math>\eta^s_y</math>, <math>\eta^s_t</math> are factors multiplied on the moment of inertia <math>I_x</math>, <math>I_y</math>, <math>I_z</math> in the stiffness matrix and inserted in the damping matrix.</p> <p>! Pay attention, the mass/stiffness proportional damping is not contributing when a mbody consist of multiple bodies !</p> <ol style="list-style-type: none"> <li>1. <math>\eta^m_x</math></li> <li>2. <math>\eta^m_y</math></li> <li>3. <math>\eta^m_t</math></li> <li>4. <math>\eta^s_x</math></li> <li>5. <math>\eta^s_y</math></li> <li>6. <math>\eta^s_t</math></li> </ol>
	copy_main_body	<p>Command that can be used if properties from a previously defined body shall be copied. The name command still have to be present, all other data are overwritten.</p> <ol style="list-style-type: none"> <li>1. Main_body identification name of main_body that is copied.</li> </ol>
	gravity	<ol style="list-style-type: none"> <li>1. Specification of gravity (directed towards <math>z_G</math>). NB! this gravity command only affects the present main body. Default=9.81 [m/s<sup>2</sup>]</li> </ol>
	concentrated_mass	<p>Concentrated masses and inertias can be attached to the structure. The offset distance from the node to the center of mass is given in the body’s coordinates system. The moments and products of inertia is given around the center of mass in the body’s coordinates system.</p> <ol style="list-style-type: none"> <li>1. Node number to which the inertia is attached.</li> <li>2. Offset distance x-direction [m]</li> <li>3. Offset distance y-direction [m]</li> <li>4. Offset distance z-direction [m]</li> <li>5. Mass [kg]</li> <li>6. <math>I_{xx}</math> [kg m<sup>2</sup>]</li> <li>7. <math>I_{yy}</math> [kg m<sup>2</sup>]</li> <li>8. <math>I_{zz}</math> [kg m<sup>2</sup>]</li> <li>9. <math>I_{xy}</math> [kg m<sup>2</sup>] – optional</li> <li>10. <math>I_{xz}</math> [kg m<sup>2</sup>] – optional</li> <li>11. <math>I_{yz}</math> [kg m<sup>2</sup>] – optional</li> </ol>
	external_bladedata_dll	<p>Blade structural data are found in an external encrypted dll. If this command is present only these other command lines need to be present (name, type, nbodies, node_distribution and a damping command line).</p> <ol style="list-style-type: none"> <li>1. Company name (that has been granted a password, eg. dtu).</li> <li>2. Password for opening this specific dll, eg. test1234</li> <li>3. path and filename for the dll. eg. ./data/encr_blade_data.dll</li> </ol>

### Sub sub command block – timoschenko\_input

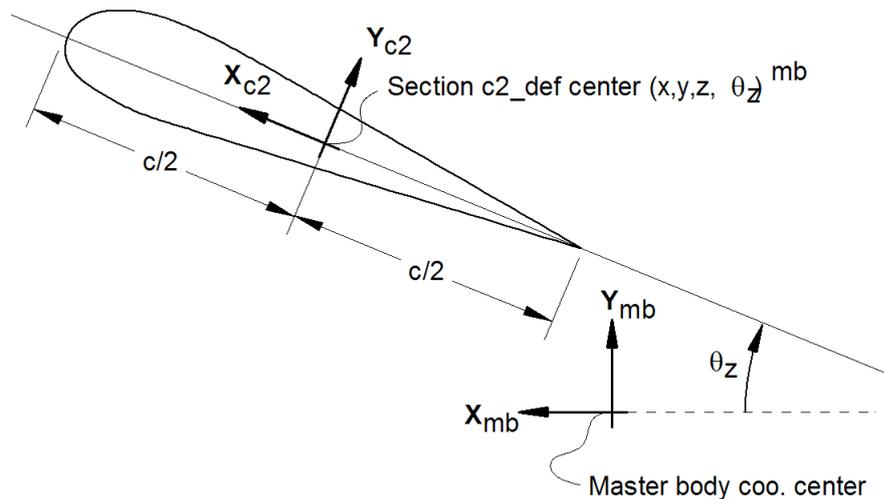
Block containing information about location of the file containing distributed beam property data and the data set requested.

Obl.	Command name	Explanation
*	filename	1. Filename incl. relative path to file where the distributed beam input data are listed (example ./data/hawc2_st.dat)
	FPM	Logic command for Fully Populated Matrix beam element: 1. Write "1" to read a structural input file based on the fully populated stiffness matrix. Write "0" for the original beam model  If the command is neglected, HAWC2 will assume that the structural input file is based on the original beam model
*	set	1. Set number 2. Sub set number

### Sub sub command block – c2\_def

In this command block the definition of the centerline of the main\_body is described (position of the half chord, when the main\_body is a blade). The input data given with the sec commands below is used to define a continuous differentiable line in space using akima spline functions. This centerline is used as basis for local coordinate system definitions for sections along the structure. If two input sections are given it is assumed that all points are on a straight line. If three input sections are given points are assumed to be on the line consisted of two straight lines. If four or more input sections are given points are assumed to be on an akima interpolated spline. This spline will include a straight line if a minimum of three points on this line is defined.

Position and orientation of half chord point related to main body coo.

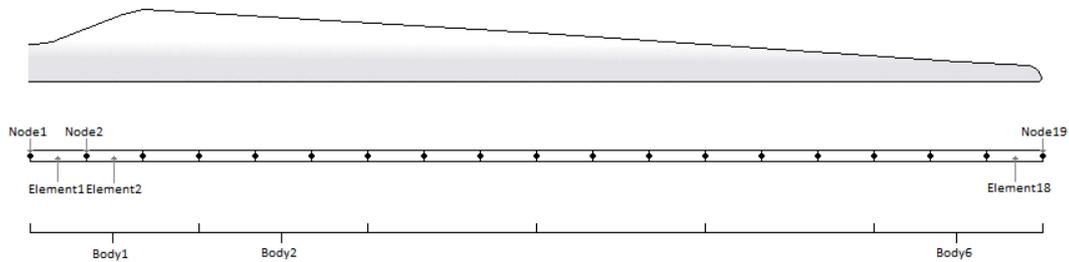


**Figure 2: Illustration of c2\_def coordinate system related to main body coordinates. The blade z-coordinate has to be positive from root towards the tip.**

Obl.	Command name	Explanation
*	nsec	Must be the present before a “sec” command. 1. Number of section commands given below
*	sec	Command that must be repeated “nsec” times. Minimum 4 times. 1. Number 2. x-pos [m] 3. y-pos [m] 4. z-pos [m] 5. $\theta_z$ [deg]. Angle between local x-axis and main_body x-axis in the main_body x-y coordinate plane. For a straight blade this angle is the aerodynamic twist. Note that the sign is positive around the z-axis, which is opposite to traditional notation for etc. a pitch angle.

Here is an illustration of how a blade can be defined with respect to discretisation of bodies, nodes and elements.

Main Body: Blade1



Here is an example of this written into the htc-input file.

```

begin main_body;
name      blad1 ;
type      timoschenko ;
nbodies   6 ;
node_distribution  c2_def;
damping_posdef  1.17e-4 5.77e-5 6.6e-6 6.6e-4 5.2e-4 6.5e-4 ;
begin timoschenko_input ;
filename ./data/st_file.txt ;
    FPM 0; (optional, when parameter is 0)
    set 1 1 ;          set subset
end timoschenko_input;
begin c2_def;          Definition of centerline (main_body coordinates)
    nsec 19 ;
    sec 1      -0.0000      0.0000      0.000      0.000      ;
    sec 2      -0.0041      0.0010      3.278      -13.590      ;
    sec 3      -0.1048      0.0250      6.556      -13.568      ;
    sec 4      -0.2582      0.0492      9.833      -13.564      ;
    sec 5      -0.4694      0.0587      13.111     -13.546      ;
    sec 6      -0.5689      0.0957      16.389     -11.406      ;
    sec 7      -0.5455      0.0883      19.667     -10.145      ;
    sec 8      -0.5246      0.0732      22.944     -9.043       ;
    sec 9      -0.4362      0.0669      26.222     -7.843       ;
    sec 10     -0.4644      0.0554      29.500     -6.589       ;
    sec 11     -0.4358      0.0449      32.778     -5.447       ;
    sec 12     -0.4859      0.0347      36.056     -4.234       ;
    sec 13     -0.3759      0.0265      39.333     -3.545       ;
    sec 14     -0.3453      0.0130      42.611     -2.223       ;
    sec 15     -0.3156      0.0084      45.889     -1.553       ;
    sec 16     -0.2791      0.0044      49.167     -0.934       ;
    sec 17     -0.2675      0.0017      52.444     -0.454       ;
    sec 18     -0.1785      0.0003      55.722     -0.121       ;
    sec 19     -0.1213      0.0000      59.000     -0.000       ;
end c2_def ;
end main_body;

```

### Format definition of file including distributed beam properties

The format of this file which in the old HAWC code was known as the hawc\_st file is changed slightly for the HAWC2 new\_htc\_structure format.

In the file (which is a text file) two different datasets exist. There is a main set and a sub set. The main set is located after a “#” sign followed by the main set number. Within a main there can be as many subsets as desired. They are located after a “\$” sign followed by the local set number. The next sign of the local set number is the number of lines in the following rows that belong to this sub set.

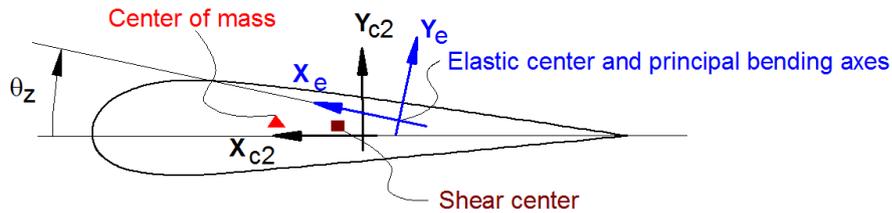
There are two types st\_file:

- The st\_file for the original HAWC2 beam element; input parameters for this model are reported in Table 1 HAWC2 original beam element structural data
- The st\_file for the new anisotropic FPM beam element; input parameters reported in
  - Table 2 New HAWC2 anisotropic beam element structural data

In general all centers are given according to the  $C_{1/2}$  center location and all other are related to the principal bending axes.

For the anisotropic beam element, centers are given according to the  $C_{1/2}$  center location, but the cross sectional stiffness matrix is given at the elastic center rotated along the principal bending axes.

Position of structural centers related to c2\_def section coo.



**Figure 3: Illustration of structural properties that in the input files are related to the c2 coordinate system**

*Table 1 HAWC2 original beam element structural data*

Column	Parameter
1	<b>r</b> , curved length distance from main_body node 1 [m]
2	<b>m</b> , mass per unit length [kg/m]
3	<b>x<sub>m</sub>, x<sub>c2</sub></b> -coordinate from $C_{1/2}$ to mass center [m]
4	<b>y<sub>m</sub>, y<sub>c2</sub></b> -coordinate from $C_{1/2}$ to mass center [m]
5	<b>r<sub>ix</sub></b> , radius of gyration related to elastic center. Corresponds to rotation about principal bending <b>x<sub>e</sub></b> axis [m]
6	<b>r<sub>iy</sub></b> , radius of gyration related to elastic center. Corresponds to rotation about principal bending <b>y<sub>e</sub></b> axis [m]
7	<b>x<sub>s</sub>, x<sub>c2</sub></b> -coordinate from $C_{1/2}$ to shear center [m]. The shear center is the point where external forces only contributes to pure bending and no torsion.
8	<b>y<sub>s</sub>, y<sub>c2</sub></b> -coordinate from $C_{1/2}$ to shear center [m]. The shear center is the point where external forces only contributes to pure bending and no torsion.
9	<b>E</b> , modulus of elasticity [N/m <sup>2</sup> ]
10	<b>G</b> , shear modulus of elasticity [N/m <sup>2</sup> ]
11	<b>I<sub>x</sub></b> , area moment of inertia with respect to principal bending <b>x<sub>e</sub></b> axis [m <sup>4</sup> ].

	<b>This is the principal bending axis most parallel to the <math>x_{c2}</math> axis</b>
12	<b><math>I_y</math>, area moment of inertia with respect to principal bending <math>y_e</math> axis [<math>m^4</math>]</b>
13	<b><math>K</math>, torsional stiffness constant with respect to <math>z_e</math> axis at the shear center [<math>m^4/\text{rad}</math>]. For a circular section only this is identical to the polar moment of inertia.</b>
14	<b><math>k_x</math> shear factor for force in principal bending <math>x_e</math> direction [-]</b>
15	<b><math>k_y</math>, shear factor for force in principal bending <math>y_e</math> direction [-]</b>
16	<b><math>A</math>, cross sectional area [<math>m^2</math>]</b>
17	<b><math>\theta_s</math>, structural pitch about <math>z_{c2}</math> axis. This is the angle between the <math>x_{c2}</math> -axis defined with the <code>c2_def</code> command and the main principal bending axis <math>x_e</math>.</b>
18	<b><math>x_e, x_{c2}</math>-coordinate from <math>C_{1/2}</math> to center of elasticity [m]. The elastic center is the point where radial force (in the <math>z</math>-direction) does not contribute to bending around the <math>x</math> or <math>y</math> directions.</b>
19	<b><math>y_e, y_{c2}</math>-coordinate from <math>C_{1/2}</math> to center of elasticity [m]. The elastic center is the point where radial force (in the <math>z</math>-direction) does not contribute to bending around the <math>x</math> or <math>y</math> directions.</b>

A small explanation about radius of gyration (also called radius of inertia) and the area moment of inertia (related to stiffness) is shown below in N.5 and N.11

- **N.5**  $r_{ix}$  [m] Radius of inertia. Related to the Moment of Inertia  $I_{xx}$  [ $kg\ m^2$ ], which gives the rotation inertia, resistance to change in rotation rate:

$$I_{xx} = \int r_{ix}^2 dm \quad \rightarrow \quad r = \sqrt{\frac{I_{xx}}{m}} = \sqrt{\frac{I_x}{A}}$$

- **N.11**  $I_x$  [ $m^4$ ] Area moment of inertia with respect to  $x_e$ . It's the second moment of area  $I_x = \int y^2 dA$ . Multiplied by Young's modulus  $E$  gives the flapwise bending stiffness:

$$\text{Stiffn}_{\text{flap}} = E \cdot I_x = \frac{M}{d^2w/d^2x}$$

$$\text{Stiffn}_{\text{edge}} = E \cdot I_y$$

$$\text{Stiffn}_{\text{tors}} = G \cdot K$$

An example of a st original beam formulation input file can be seen on the next page. The most important features to be aware of are colored with **red**.

# Risø DTU

1 main data sets available

-----  
 Here is space for comments etc

.  
 .  
 .

-----  
 #1 Main data set number 1 - an example of a shaft structure

-----  
 More comments space

r	m	x_cg	y_cg	ri_x	ri_y	x_sh	y_sh	E	G	I_x	I_y	K	k_x	k_y	A	theta_s	x_e	y_e
[m]	[kg/m]	[m]	[m]	[m]	[m]	[m]	[m]	[N/m <sup>2</sup> ]	[N/m <sup>2</sup> ]	[N/m <sup>4</sup> ]	[N/m <sup>4</sup> ]	[N/m <sup>4</sup> ]	[-]	[-]	[m <sup>2</sup> ]	[deg]	[m]	[m]
#1 10 Sub set number 1 with 10 data rows																		
0.00	100	0	0	224.18	224.18	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
0.10	100	0	0	224.18	224.18	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
0.1001	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
1.00	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
1.90	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
2.00	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
3.00	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
3.20	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
4.00	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
5.0191	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0

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 More comments space

r	m	x_cg	y_cg	ri_x	ri_y	x_sh	y_sh	E	G	I_x	I_y	K	k_x	k_y	A	theta_s	x_e	y_e
[m]	[kg/m]	[m]	[m]	[m]	[m]	[m]	[m]	[N/m <sup>2</sup> ]	[N/m <sup>2</sup> ]	[N/m <sup>4</sup> ]	[N/m <sup>4</sup> ]	[N/m <sup>4</sup> ]	[-]	[-]	[m <sup>2</sup> ]	[deg]	[m]	[m]
#2 10 As dataset 1, but stiff																		
0.00	100	0	0	224.18	224.18	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
0.10	100	0	0	224.18	224.18	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
0.1001	1	0	0	0.2	0.2	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
1.00	1	0	0	0.2	0.2	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
1.90	1	0	0	0.2	0.2	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
2.00	1	0	0	0.2	0.2	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
3.00	1	0	0	0.2	0.2	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
3.20	1	0	0	0.2	0.2	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
4.00	1	0	0	0.2	0.2	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
5.0191	1	0	0	0.2	0.2	0	0	2.10E+16	8.10E+15	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0

-----  
 More comments space

r	m	x_cg	y_cg	ri_x	ri_y	x_sh	y_sh	E	G	I_x	I_y	K	k_x	k_y	A	theta_s	x_e	y_e
[m]	[kg/m]	[m]	[m]	[m]	[m]	[m]	[m]	[N/m <sup>2</sup> ]	[N/m <sup>2</sup> ]	[N/m <sup>4</sup> ]	[N/m <sup>4</sup> ]	[N/m <sup>4</sup> ]	[-]	[-]	[m <sup>2</sup> ]	[deg]	[m]	[m]
#3 10 as data set 1 but changed mass properties																		
0.00	1000	0	0	2.2418	2.2418	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
0.10	1000	0	0	2.2418	2.2418	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
0.1001	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
1.00	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
1.90	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
2.00	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
3.00	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
3.20	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
4.00	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0
5.0191	1	0	0	0.2	0.2	0	0	2.10E+11	8.10E+10	1.00E+02	1.00E+02	0.05376	0.52	0.52	0.59	0	0.0	0.0

Table 2 New HAWC2 anisotropic beam element structural data

Column	
1	$r$ , curved length distance from main_body node 1 [m]
2	$m$ , mass per unit length [kg/m]
3	$x_m, x_{c2}$ -coordinate from $C_{1/2}$ to mass center [m]
4	$y_m, y_{c2}$ -coordinate from $C_{1/2}$ to mass center [m]
5	$r_{ix}$ , radius of gyration related to elastic center. Corresponds to rotation about principal bending $x_e$ axis [m]
6	$r_{iy}$ , radius of gyration related to elastic center. Corresponds to rotation about principal bending $y_e$ axis [m]
7	$\theta_s$ , structural pitch about $z_{c2}$ axis. This is the angle between the $x_{c2}$ -axis defined with the $c2\_def$ command and the main principal bending axis $x_e$ .
8	$x_e, x_{c2}$ -coordinate from $C_{1/2}$ to center of elasticity [m]. The elastic center is the point where radial force (in the z-direction) does not contribute to bending around the x or y directions.
9	$y_e, y_{c2}$ -coordinate from $C_{1/2}$ to center of elasticity [m]. The elastic center is the point where radial force (in the z-direction) does not contribute to bending around the x or y directions.
10	$K_{11}$ , element 1,1 of the Cross sectional stiffness matrix [ $Nm^2$ ]. <b>REMEMBER:</b> the cross sectional stiffness matrix is given at the elastic center rotated along the principal bending axes.
11	$K_{12}$ , element 1,2 of the Cross sectional stiffness matrix [ $Nm^2$ ].
12	$K_{13}$ , element 1,3 of the Cross sectional stiffness matrix [ $Nm^2$ ].
13	$K_{14}$ , element 1,4 of the Cross sectional stiffness matrix [ $Nm^2$ ].
14	$K_{15}$ , element 1,5 of the Cross sectional stiffness matrix [ $Nm^2$ ].
15	$K_{16}$ , element 1,6 of the Cross sectional stiffness matrix [ $Nm^2$ ].
16	$K_{22}$ , element 2,2 of the Cross sectional stiffness matrix [ $Nm^2$ ].
17	$K_{23}$ , element 2,3 of the Cross sectional stiffness matrix [ $Nm^2$ ].
18	$K_{24}$ , element 2,4 of the Cross sectional stiffness matrix [ $Nm^2$ ].
19	$K_{25}$ , element 2,5 of the Cross sectional stiffness matrix [ $Nm^2$ ].
20	$K_{26}$ , element 2,6 of the Cross sectional stiffness matrix [ $Nm^2$ ].
21	$K_{33}$ , element 2,3 of the Cross sectional stiffness matrix [ $Nm^2$ ].
22	$K_{34}$ , element 2,4 of the Cross sectional stiffness matrix [ $Nm^2$ ].
23	$K_{35}$ , element 2,5 of the Cross sectional stiffness matrix [ $Nm^2$ ].
24	$K_{36}$ , element 2,6 of the Cross sectional stiffness matrix [ $Nm^2$ ].
25	$K_{44}$ , element 2,4 of the Cross sectional stiffness matrix [ $Nm^2$ ].
26	$K_{45}$ , element 2,5 of the Cross sectional stiffness matrix [ $Nm^2$ ].
27	$K_{46}$ , element 2,6 of the Cross sectional stiffness matrix [ $Nm^2$ ].
28	$K_{55}$ , element 2,5 of the Cross sectional stiffness matrix [ $Nm^2$ ].
29	$K_{56}$ , element 2,6 of the Cross sectional stiffness matrix [ $Nm^2$ ].
30	$K_{66}$ , element 2,6 of the Cross sectional stiffness matrix [ $Nm^2$ ].

An example of a st anisotropic beam formulation input file can be seen on the next page.



### Sub sub command – damping\_distributed

In this command block, Rayleigh damping parameters can be defined as function of blade length, hence damping parameters can be different at root of tip of a blade.

Obl.	Command name	Explanation
*	nsec	Number of input lines
*	sec	This command must be repeated nsec times. <ol style="list-style-type: none"> <li>1. <math>r/R</math>. Non-dim distance from node 1 to node N.</li> <li>2. <math>k_x</math> Stiffness proportional damping around x</li> <li>3. <math>k_y</math> Stiffness proportional damping around y</li> <li>4. <math>k_z</math> Stiffness proportional damping around z</li> </ol>

### Sub sub command – damping\_posdef\_distributed

In this command block, Rayleigh damping parameters can be defined as function of blade length, hence damping parameters can be different at root of tip of a blade.

Obl.	Command name	Explanation
*	nsec	Number of input lines
*	sec	This command must be repeated nsec times. <ol style="list-style-type: none"> <li>1. <math>r/R</math>. Non-dim distance from node 1 to node N.</li> <li>2. <math>k_x</math> Stiffness proportional damping around x</li> <li>3. <math>k_y</math> Stiffness proportional damping around y</li> <li>4. <math>k_z</math> Stiffness proportional damping around z</li> </ol>

### Sub command - orientation

In this command block the orientation (regarding position and rotation) of every main\_body are specified.

### Sub sub command - base

The orientation of a main\_body to which all other bodies are linked – directly or indirectly.

Obl.	Command name	Explanation
*	mbdy <small>(old command name <b>body</b> still usable)</small>	<ol style="list-style-type: none"> <li>1. Main_body name that is declared to be the base of all bodies (normally the tower or foundation)</li> </ol>
*	inipos	Initial position in global coordinates. <ol style="list-style-type: none"> <li>1. x-pos [m]</li> <li>2. y-pos [m]</li> <li>3. z-pos [m]</li> </ol>
♣	mbdy_eulerang <small>(old command name <b>body_eulerang</b> still usable)</small>	Command that can be repeated as many times as needed. All following rotation are given as a sequence of euler angle rotations. All angle can be filled in (rotation order x,y,z), but it is recommended only to give a value different from zero on one of the angles and reuse the command if several rotations are needed. <ol style="list-style-type: none"> <li>1. <math>\theta_x</math> [deg]</li> <li>2. <math>\theta_y</math> [deg]</li> <li>3. <math>\theta_z</math> [deg]</li> </ol>
♣	body_eulerpar	The rotation is given as euler parameters (quaternions) directly (global coo). <ol style="list-style-type: none"> <li>1. <math>r_0</math></li> <li>2. <math>r_1</math></li> <li>3. <math>r_2</math></li> <li>4. <math>r_3</math></li> </ol>

♣	mbody_axisangle  (old command name <b>body_axisangle</b> still usable)	Command that can be repeated as many times as needed. A version of the euler parameters where the input is a rotation vector and the rotation angle of this vector. <ol style="list-style-type: none"> <li>1. x-value</li> <li>2. y-value</li> <li>3. z-value</li> <li>4. angle [deg]</li> </ol>
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♣ One of these commands must be present.

## Sub sub command - relative

This command block can be repeated as many times as needed. However the orientation of every main\_body should be described.

Obl.	Command name	Explanation
*	mbdy1  (old command name <b>body1</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name to which the next main_body is attached.</li> <li>2. Node number of body1 that is used for connection. ("last" can be specified which ensures that the last node on the main_body is used).</li> </ol>
*	mbdy2  (old command name <b>body2</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name of the main_body that is positioned in space by the relative command.</li> <li>2. Node number of body2 that is used for connection. ("last" can be specified which ensures that the last node on the main_body is used).</li> </ol>
♣	mbdy2_eulerang  (old command name <b>body2_eulerang</b> still usable)	<p>Command that can be repeated as many times as needed. All following rotation are given as a sequence of euler angle rotations. All angle can be filled in (rotation order x,y,z), but it is recommended only to give a value different from zero on one of the angles and reuse the command if several rotations are needed. Until a rotation command is specified body2 has same coo. as body1. Rotations are performed in the present body2 coo. system.</p> <ol style="list-style-type: none"> <li>1. <math>\theta_x</math> [deg]</li> <li>2. <math>\theta_y</math> [deg]</li> <li>3. <math>\theta_z</math> [deg]</li> </ol>
♣	mbdy2_eulerpar  (old command name <b>body2_eulerpar</b> still usable)	<p>The rotation is given as euler parameters (quaternions) directly (global coo).</p> <ol style="list-style-type: none"> <li>1. <math>r_0</math></li> <li>2. <math>r_1</math></li> <li>3. <math>r_2</math></li> <li>4. <math>r_3</math></li> </ol>
♣	mbdy2_axisangle  (old command name <b>body2_axisangle</b> still usable)	<p>Command that can be repeated as many times as needed. A version of the euler parameters where the input is a rotation vector and the rotation angle of this vector. Until a rotation command is specified main_body2 has same coo. as main_body1. Rotations are performed in the present main_body2 coo. system.</p> <ol style="list-style-type: none"> <li>1. x-value</li> <li>2. y-value</li> <li>3. z-value</li> <li>4. angle [deg]</li> </ol>
	mbdy2_ini_rotvec_d1  (old command name <b>body2_ini_rotvec_d1</b> still usable)	<p>Initial rotation velocity of main body and all subsequent attached bodies. A rotation vector is set up and the size of vector (the rotational speed) is given. The coordinate system used is main_body2 coo.</p> <ol style="list-style-type: none"> <li>1. x-value</li> <li>2. y-value</li> <li>3. z-value</li> <li>4. Vector size (rotational speed [rad/s])</li> </ol>
	relpos	<p>Vector from coupling node of mbdy 1 to coupling node of mbdy 2 in mbdy2 coo system in case a certain distance between these nodes is required. (Default for overlapping coupling nodes, this vector is (0,0,0))</p> <ol style="list-style-type: none"> <li>1. x-value</li> <li>2. y-value</li> <li>3. z-value</li> </ol>

## Sub command - constraint

In this block constraints between the main\_bodies and to the global coordinate system are defined.

### Sub sub command – fix0

This constraint fix node number 1 of a given main\_body to ground.

Obl.	Command name	Explanation
*	mbdy  (old command name <b>body</b> still usable)	Name of main body that is fixed to ground at node 1
	disable_at	Time to which constraint can be disabled 1. $t_0$

### Sub sub command – fix1

This constraint fix a given node on one main\_body to another main\_body's node.

Obl.	Command name	Explanation
*	mbdy1  (old command name <b>body1</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name to which the next main_body is fixed.</li> <li>2. Node number of main_body1 that is used for the constraint. ("last" can be specified which ensures that the last node on the main_body is used).</li> </ol>
*	mbdy2  (old command name <b>body2</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name of the main_body that is fixed to main_body1.</li> <li>2. Node number of main_body2 that is used for the constraint. ("last" can be specified which ensures that the last node on the main_body is used).</li> </ol>
	disable_at	Time to which constraint can be disabled 1. $t_0$

### Sub sub command – fix2

This constraint fix a node 1 on a main\_body to ground in x,y,z direction. The direction that is free or fixed is optional.

Obl.	Command name	Explanation
*	mbdy  (old command name <b>body</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name to which node 1 is fixed.</li> </ol>
*	dof	Direction in global coo that is fixed in translation <ol style="list-style-type: none"> <li>1. x-direction (0=free, 1=fixed)</li> <li>2. y-direction (0=free, 1=fixed)</li> <li>3. z-direction (0=free, 1=fixed)</li> </ol>

### Sub sub command – fix3

This constraint fix a node to ground in tx,ty,tz rotation direction. The rotation direction that is free or fixed is optional.

Obl.	Command name	Explanation
*	mbdy  (old command name <b>body</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name to which node 1 is fixed.</li> <li>2. Node number</li> </ol>
*	dof	Direction in global coo that is fixed in rotation

		<ol style="list-style-type: none"> <li>1. tx-rot.direction (0=free, 1=fixed)</li> <li>2. ty-rot.direction (0=free, 1=fixed)</li> <li>3. tz-rot.direction (0=free, 1=fixed)</li> </ol>
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### Sub sub command – fix4

Constraint that locks a node on a body to another node in translation but not rotation with a pre-stress feature. The two nodes will start at the defined positions to begin with but narrow the distance until fully attached at time T.

Obl.	Command name	Explanation
*	mbdy1  (old command name <b>body1</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name to which the next main_body is fixed.</li> <li>2. Node number of main_body1 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).</li> </ol>
*	mbdy2  (old command name <b>body2</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name of the main_body that is fixed to body1.</li> <li>2. Node number of main_body2 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).</li> </ol>
	time	<ol style="list-style-type: none"> <li>3. Time for the pre-stress process. Default=2sec</li> </ol>

### Sub sub command – bearing1

Constraint with properties as a bearing without friction. A sensor with same identification name as the constraint is set up for output purpose.

Obl.	Command name	Explanation
*	name	<ol style="list-style-type: none"> <li>1. Identification name</li> </ol>
*	mbdy1  (old command name <b>body1</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name to which the next main_body is fixed with bearing1 properties.</li> <li>2. Node number of main_body1 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).</li> </ol>
*	mbdy2  (old command name <b>body2</b> still usable)	<ol style="list-style-type: none"> <li>1. Main_body name of the main_body that is fixed to body1 with bearing1 properties.</li> <li>2. Node number of main_body2 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).</li> </ol>
*	bearing_vector	<p>Vector to which the free rotation is possible. The direction of this vector also defines the coo to which the output angle is defined.</p> <ol style="list-style-type: none"> <li>1. Coor. system used for vector definition (0=global,1=mbdy1,2=mbdy2)</li> <li>2. x-axis</li> <li>3. y-axis</li> <li>4. z-axis</li> </ol>
	disable_at	<p>Time to which constraint can be disabled</p> <ol style="list-style-type: none"> <li>1. <math>t_0</math></li> </ol>

## Sub sub command – bearing2

This constraint allows a rotation where the angle is directly specified by an external dll action command.

Obl.	Command name	Explanation
*	name	1. Identification name
*	mbdy1  (old command name <b>body1</b> still usable)	1. Main_body name to which the next main_body is fixed with bearing2 properties. 2. Node number of main_body1 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).
*	mbdy2  (old command name <b>body2</b> still usable)	1. Main_body name of the main_body that is fixed to main_body1 with bearing1 properties. 2. Node number of main_body2 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).
*	bearing_vector	Vector to which the rotation occur. The direction of this vector also defines the coo to which the output angle is defined. 1. Coo. system used for vector definition (0=global,1=mbdy1, 2=mbdy2) 2. x-axis 3. y-axis 4. z-axis
	disable_at	Time to which constraint can be disabled 1. $t_0$

## Sub sub command – bearing3

This constraint allows a rotation where the angle velocity is kept constant throughout the simulation.

Obl.	Command name	Explanation
*	name	1. Identification name
*	mbdy1  (old command name <b>body1</b> still usable)	1. Main_body name to which the next main_body is fixed with bearing3 properties. 2. Node number of main_body1 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).
*	mbdy2  (old command name <b>body2</b> still usable)	1. Main_body name of the main_body that is fixed to body1 with bearing3 properties. 2. Node number of main_body2 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).
*	bearing_vector	Vector to which the rotation occur. The direction of this vector also defines the coo to which the output angle is defined. 1. Coo. system used for vector definition (0=global,1=body1,2=body2) 2. x-axis 3. y-axis 4. z-axis
*	omegas	1. Rotational speed [rad/sec]

## Sub sub command – bearing4

This constraint is a cardan shaft constraint. Locked in relative translation. Locked in rotation around one vector and allows rotation about the two other directions.

Obl.	Command name	Explanation
*	name	1. Identification name
*	mbdy1  (old command name <b>body1</b> still usable)	1. Main_body name to which the next main_body is fixed with bearing3 properties. 2. Node number of main_body1 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).
*	mbdy2  (old command name <b>body2</b> still usable)	1. Main_body name of the main_body that is fixed to body1 with bearing3 properties. 2. Node number of main_body2 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).
*	bearing_vector	Vector to which the rotation is locked. The rotation angle and velocity can be outputted around the two perpendicular directions. 1. Coor. system used for vector definition (0=global,1=mbdy1, 2=mbdy2) 2. x-axis 3. y-axis 4. z-axis

## Sub sub command – bearing5

This constraint is a spherical constraint. Locked in relative translation. Free in rotation around all three axis, but only sensor on the main rotation direction.

Obl.	Command name	Explanation
*	name	1. Identification name
*	mbdy1  (old command name <b>body1</b> still usable)	1. Main_body name to which the next main_body is fixed with bearing3 properties. 2. Node number of main_body1 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).
*	mbdy2  (old command name <b>body2</b> still usable)	1. Main_body name of the main_body that is fixed to body1 with bearing3 properties. 2. Node number of main_body2 that is used for the constraint. (“last” can be specified which ensures that the last node on the main_body is used).
*	bearing_vector	Vector to which the rotation is locked. The rotation angle and velocity can be outputted around the two perpendicular directions. 1. Coor. system used for vector definition (0=global,1=mbdy1, 2=mbdy2) 2. x-axis 3. y-axis 4. z-axis

## DLL control

This block contains the possible Dynamic Link Library formats accessible for the user. The DLL's are mainly used to control the turbine speed and pitch, but since the DLL format is very general, other use is possible too e.g. external loading of the turbine. Since the HAWC2 core has no information about external stiffness or inertia we have experienced some issues with the solver if the DLL includes high stiffness terms or especially large inertia terms. The new `type2_dll` interface is slightly more stable related to the solver than the `hawc_dll` interface.

### Main command block – dll

So far only one DLL format is available, which is the `hawc_dll` format listed below.

### Sub command block – hawc\_dll

In the HAWC\_DLL format a subroutine within an externally written DLL is setup. In this subroutine call two one-dimensional arrays are transferred between the HAWC2 core and the DLL procedure. The first contains data going from the HAWC2 core to the DLL and the other contains data going from the DLL to the core. It is very important to notice that the data are transferred between HAWC2 and the DLL in every timestep and every iteration. The user should handle the iteration inside the DLL.

Two more subroutines are called if they are present inside the dll file:

The first is an initialisation call including a text string written in the `init_string` in the commands below. This could be the name of a file holding local input parameters to the data transfer subroutine. This call is only performed once. The name of this subroutine is the same name as the data transfer subroutine defined with the command `dll_subroutine` below with the extra name `'_init'`, hence is the data transfer subroutine is called `'test'`, the initialisation subroutine will be `'test_init'`.

The second subroutine is a message exchange subroutine, where messages written in the DLL can be send to the HAWC2 core for logfile writing. The name of this subroutine is the same name as the data transfer subroutine defined with the command `dll_subroutine` below with the extra name `'_message'`, hence is the data transfer subroutine is called `'test'`, the initialisation subroutine will be `'test_message'`.

The command block can be repeated as many times as desired. Reference number to DLL is same order as listed, starting with number 1. However it is recommended to refer the DLL using the name feature which in many cases can avoid confusion.

Obl.	Command name	Explanation
	name	1. Reference name of this DLL (to be used with DLL output commands)
*	filename	1. Filename incl. relative path of the DLL (example ./DLL/control.dll)
*	dll_subroutine	1. Name of subroutine in DLL that is addressed (remember to specify the name in the DLL with small letters!)
*	arraysizes	1. size of array with outgoing data 2. size of array with ingoing data
	deltat	1. Time between dll calls. Must correspond to the simulation sample frequency or be a multiple of the time step size. If deltat=0.0 or the deltat command line is omitted the HAWC2 code calls the dll subroutine at every time step.
	init_string	1. Text string (max 256 characters) that will be transferred to the DLL through the subroutine 'subroutine_init'. Subroutine is the name given in in the command dll_subroutine. No blanks can be included.

## Sub command block – type2\_dll

This dll interface is an updated slightly modified version of the hawc\_dll interface. In the TYPE2\_DLL format a subroutine within an externally written DLL is setup. In this subroutine call two one-dimensional arrays are transferred between the HAWC2 core and the DLL procedure. The first contains data going from the HAWC2 core to the DLL and the other contains data going from the DLL to the core. It is very important to notice that the data are transferred between HAWC2 and the DLL in the first call of every timestep where the out-going variables are based on last iterated values from previous time step. The sub command **output** and **actions** are identical for both the hawc\_dll and the type2\_dll interfaces.

In the dll connected with using the type2\_dll interface two subroutines should be present. An *initialization* routine called only once before the time simulation begins, and an *update* routine called in every time step. The format in the calling of these two subroutines are identical where two arrays of double precision is exchanged. The subroutine uses the **cdecl** calling convention.

Obl.	Command name	Explanation
	name	1. Reference name of this DLL (to be used with DLL output commands)
*	filename	1. Filename incl. relative path of the DLL (example ./DLL/control.dll)
*	dll_subroutine_init	1. Name of initialization subroutine in DLL that is addressed (remember to specify the name in the DLL with small letters!)
*	dll_subroutine_update	1. Name of subroutine in DLL that is addressed at every time step (remember to specify the name in the DLL with small letters!)
*	arraysizes_init	1. size of array with outgoing data in the initialization call 2. size of array with ingoing data in the initialization

		call
*	arraysizes_update	<ol style="list-style-type: none"> <li>1. size of array with outgoing data in the update call</li> <li>2. size of array with ingoing data in the update call</li> </ol>
	deltat	<ol style="list-style-type: none"> <li>1. Time between dll calls. Must correspond to the simulation sample frequency or be a multiple of the time step size. If deltat=0.0 or the deltat command line is omitted the HAWC2 code calls the dll subroutine at every time step.</li> </ol>

when using the type2\_dll interface the values transferred to the DLL in the initialization phase is done using a sub command block called **init**. The commands for this subcommand block is identical to the **output** subcommand explained below, but only has the option of having the *constant* output sensor available. An example is given for a small dll that is used for converting rotational speed between high speed and low speed side of a gearbox.:

```
begin dll;
  begin type2_dll;
    name hss_convert;
    filename ./control/hss_convert.dll ;
    arraysizes_init 3 1 ;
    arraysizes_update 2 2 ;
    begin init;
      constant 1 2.0 ;      number of used sensors - in this case only 1
      constant 2 35.110;   gearbox ratio
      constant 3 35.110;   gearbox ratio
    end init;
    begin output;
      constraint bearing1 shaft_rot 2 only 2 ;   rotor speed in rpm
      constraint bearing1 shaft_rot 3 only 2 ;   rotor speed in rad/s
    end output;
  ;
  begin actions;
  ;   rotor speed in rpm * gear_ratio
  ;   rotor speed in rad/s * gear_ratio
  end actions;
  end type2_dll;
end dll;
```

### Sub command block - output

In this block the same sensors are available as when data results are written to a file with the main block command **output**, see page 85++. The order of the sensors in the data array is continuously increased as more sensors are added.

### Sub command block - actions

In this command block variables inside the HAWC2 code is changed depending of the specifications. This command block can be used for the hawc\_dll interface as well as the type2\_dll interface. An action commands creates a handle to the HAWC2 model to which a variable in the input array from the DLL is linked.

**!NB** in the command name two separate words are present.

Obl.	Command name	Explanation
	aero beta	<p>The flap angle beta is set for a trailing edge flap section (is the mhhmagf stall model is used). The angle is positive towards the pressure side of the profile. Unit is [deg]</p> <ol style="list-style-type: none"> <li>1. Blade number</li> <li>2. Flap section number</li> </ol>

Obl.	Command name	Explanation
	body force_ext	An external force is placed on the structure. Unit is [N]. <ol style="list-style-type: none"> <li>body name</li> <li>node number</li> <li>componet (1 = <math>F_x</math>, 2 = <math>F_y</math>, 3 = <math>F_z</math>)</li> </ol>
	body moment_ext	An external moment is placed on the structure. Unit is [Nm]. <ol style="list-style-type: none"> <li>body name</li> <li>node number</li> <li>component (1 = <math>M_x</math>, 2 = <math>M_y</math>, 3 = <math>M_z</math>)</li> </ol>
	body force_int	An external force with a reaction component is placed on the structure. Unit is [N]. <ol style="list-style-type: none"> <li>body name for action force</li> <li>node number</li> <li>component (1 = <math>F_x</math>, 2 = <math>F_y</math>, 3 = <math>F_z</math>)</li> <li>body name for reaction force</li> <li>Node number</li> </ol>
	body moment_int	An external moment with a reaction component is placed on the structure. Unit is [N]. <ol style="list-style-type: none"> <li>body name for action moment</li> <li>node number</li> <li>component (1 = <math>M_x</math>, 2 = <math>M_y</math>, 3 = <math>M_z</math>)</li> <li>body name for reaction moment</li> <li>Node number</li> </ol>
	body bearing_angle	A bearing either defined through the new structure format through bearing2 or through the old structure format (spitch1=pitch angle for blade 1, spitch2=pitch angle for blade 2,...). The angle limits are so far [0-90deg]. <ol style="list-style-type: none"> <li>Bearing name</li> </ol>
	mbdy force_ext	An external force is placed on the structure. Unit is [N]. <ol style="list-style-type: none"> <li>main body name</li> <li>node number on main body</li> <li>component (1 = <math>F_x</math>, 2 = <math>F_y</math>, 3 = <math>F_z</math>) , if negative number the force is inserted with opposite sign.</li> <li>coordinate system (possible options are: mbdy name,"global","local"). "local" means local element coo on the inner element (on the element indexed 1 lower that the node number). One exception if node number =1 then the element nr. also equals 1.</li> </ol>
	mbdy moment_ext	An external moment is placed on the structure. Unit is [Nm]. <ol style="list-style-type: none"> <li>main body name</li> <li>node number on main body</li> <li>component (1 = <math>M_x</math>, 2 = <math>M_y</math>, 3 = <math>M_z</math>) , if negative number the moment is inserted with opposite sign.</li> <li>coordinate system (possible options are: mbdy name,"global","local"). "local" means local element coo on the inner element (on the element indexed 1 lower that the node number). One exception if node number =1 then the element nr. also equals 1.</li> </ol>

Obl.	Command name	Explanation
	mbdy force_int	An internal force with a reaction component is placed on the structure. Unit is [N]. <ol style="list-style-type: none"> <li>1. main body name for action force</li> <li>2. node number on main body</li> <li>3. component (1 = <math>F_x</math>, 2 = <math>F_y</math>, 3 = <math>F_z</math>), if negative number the force is inserted with opposite sign.</li> <li>4. coordinate system (possible options are: mbdy name,"global","local"). "local" means local element coo on the inner element (on the element indexed 1 lower than the node number). One exception if node number =1 then the element nr. also equals 1.</li> <li>5. main body name for reaction force</li> <li>6. Node number on this main body</li> </ol>
	mbdy moment_int	An internal force with a reaction component is placed on the structure. Unit is [Nm]. <ol style="list-style-type: none"> <li>1. main body name for action moment</li> <li>2. node number on main body</li> <li>3. component (1 = <math>M_x</math>, 2 = <math>M_y</math>, 3 = <math>M_z</math>), if negative number the moment is inserted with opposite sign.</li> <li>4. coordinate system (possible options are: mbdy name,"global","local"). "local" means local element coo on the inner element (on the element indexed 1 lower than the node number). One exception if node number =1 then the element nr. also equals 1.</li> <li>5. main body name for reaction moment</li> <li>6. Node number on this main body</li> </ol>
	constraint bearing2 angle	The angle of a bearing2 constraint is set. The angle limits are so far [+/-90deg]. <ol style="list-style-type: none"> <li>1. Bearing name</li> </ol>
	body printvar	Variable is just echoed on the screen. No parameters.
	body ignore	<ol style="list-style-type: none"> <li>1. Number of consecutive array spaces that will be ignored</li> </ol>
	mbdy printvar	Variable is just echoed on the screen. No parameters.
	mbdy ignore	<ol style="list-style-type: none"> <li>1. Number of consecutive array spaces that will be ignored</li> </ol>
	general printvar	Variable is just echoed on the screen. No parameters.
	general ignore	<ol style="list-style-type: none"> <li>1. Number of consecutive array spaces that will be ignored</li> </ol>
	stop_simulation	Logical switch. If value is 1 the simulation will be stopped and output written.
	wind printvar	Variable is just echoed on the screen. No parameters.
	wind windspeed_u	External contribution to wind speed in u-direction [m/s]
	wind winddir	External contribution to the wind direction (turb. box is also rotated) [°]

## HAWC\_DLL format example written in FORTRAN 90

```
subroutine test(n1,array1,n2,array2)
implicit none
!DEC$ ATTRIBUTES DLLEXPORT, ALIAS:'test'::test
integer*4      :: n1, &      ! Dummy integer value containing the array size of array1
                n2          ! Dummy integer value containing the array size of array2
real*4,dimension(10) :: array1 ! fixed-length array, data from HAWC2 to DLL
! - in this case with length 10
real*4,dimension(5)  :: array2 ! fixed-length array, data from DLL to HAWC2
! - in this case with length 5

! Code is written here

end subroutine test

!-----

Subroutine test_init(string256)
Implicit none
!DEC$ ATTRIBUTES DLLEXPORT, ALIAS:'test_init'::test_init
Character*256 :: string256

! Code is written here

End subroutine test_init

!-----

Subroutine test_message(string256)
Implicit none
!DEC$ ATTRIBUTES DLLEXPORT, ALIAS:'test_message'::test_message
Character*256 :: string256

! Code is written here

End subroutine test_message
```

## HAWC\_DLL format example written in Delphi / Lazarus / Pascal

```
library test_dll;

type
  array_10 = array[1..10] of single;
  array_5  = array[1..5] of single;
  ts       = array[0..255] of char;

Procedure test(var n1:integer;var array1 : array_10;
              var n2:integer;var array2 : array_5);stdcall;
// n1 is a dummy integer value containing the size of array1
// n2 is a dummy integer value containing the size of array2
begin
  // Code is written here

end;

//-----

Procedure test_init(var string256:ts; length:integer);stdcall;
var
  init_str:string[255]
begin
  init_str=strpas(string256);
  // Code is written here
  writeln(init_str);
end;

//-----

Procedure test_message(var string256:ts; length:integer);stdcall;
var
  message_str:string;
begin
  // Code is written here
  message_str:='This is a test message';
  strPCopy(string256,message_str);
end;

exports test,test_init,test_message;

begin
  writeln('The DLL pitchservo.dll is loaded with succes');

  // Initialization of variables can be performed here
end;

end.
```

## HAWC\_DLL format example written in C

```
extern "C" void __declspec(dllexport) __cdecl test(int &size_of_Data_in, float Data_in[], int
&size_of_Data_out, float Data_out[])
{
    for (int i=0; i<size_of_Data_out; i++) Data_out[i]=0.0;
    //
    printf("size_of_Data_in          %d:          \n",size_of_Data_in);
    printf("Data_in                  %g:          \n",Data_in[0]);
    printf("size_of_Data_out          %d:          \n",size_of_Data_out);
    printf("Data_out          %g: \n",Data_out[0]);
}

extern "C" void __declspec(dllexport) __cdecl test_init(char* pString, int length)
{
    // Define buffer (make room for NULL-char)
    const int max_length = 256;
    char buffer[max_length+1];
    //
    // Print the length of pString
    printf("test_init::length = %d\n",length);
    //
    // Transfer string
    int nchar = min(max_length, length);
    memcpy(buffer, pString, nchar);
    //
    // Add NULL-char
    buffer[nchar] = '\0';
    //
    // Print it...
    printf("%s\n",buffer);
}

extern "C" void __declspec(dllexport) __cdecl test_message(char* pString, int max_length)
{
    // test message (larger than max_length)
    char pmessage[] = "This is a test message "
        "and it continues and it continues and it continues "
        "and it continues and it continues and it continues "
        "and it continues and it continues and it continues "
        "and it continues and it continues and it continues "
        "and it continues and it continues and it continues "
        "and it continues and it continues and it continues ";

    // Check max length - transfer only up to max_length number of chars
    int nchar = min((size_t)max_length, strlen(pmessage)); // nof chars to transfer
    // (<= max_length)
    memcpy(pString, pmessage, nchar);
    //
    // Add NULL-char if string space allows it (FORTRAN interprets a NULL-char as
    // the end of the string)
    if (nchar < max_length) pString[nchar] = '\0';
}
```

## TYPE2\_dll written in Delphi / Lazarus / Delphi

```
library hss_convert;

uses
  SysUtils,
  Classes,
  Dialogs;

Type
  array_1000 = array[0..999] of double;
Var
  factor : array of double;
  nr : integer;
  {$R *.res}

procedure initialize(var InputSignals: array_1000;var OutputSignals: array_1000); cdecl;
var
  i : integer;
begin
  nr:=trunc(inputsignals[0]);
  if nr>0 then begin
    setlength(factor,nr);
    for i:=1 to nr do
      factor[i-1]:=Inputsignals[i];
    outputsignals[0]:=1.0;
    end else outputsignals[0]:=0.0;
  end;

procedure update(var InputSignals: array_1000;var OutputSignals: array_1000); cdecl;
var
  i : integer;
begin
  for i:=0 to nr-1 do begin
    OutputSignals[i] := InputSignals[i]*factor[i];
  end;
end;

exports Initialize,Update;

begin
  // Main body
end.
```

## TYPE2\_dll written in C

```
extern "C" void __declspec(dllexport) __cdecl initialize(dfloat *Data_in, dfloat *Data_out)
{ for (int i=0; i<8; i++) Data_out[0]+=Data_in[i];
}

extern "C" void __declspec(dllexport) __cdecl update(dfloat *Data_in, dfloat *Data_out)
{ for (int i=0; i<25; i++) Data_out[0]+=Data_in[i];
  Data_out[8]=123;
}
```

## TYPE2\_DLL format example written in FORTRAN 90

```
subroutine initialize(array1,array2)
implicit none
!DEC$ ATTRIBUTES DLLEXPORT, C, ALIAS:'initialize'::initialize
real*8,dimension(1000) :: array1 ! fixed-length array, data from HAWC2 to DLL
! - in this case with length 1000
real*8,dimension(1)    :: array2 ! fixed-length array, data from DLL to HAWC2
! - in this case with length 1

! Code is written here

end subroutine initialize

!-----

subroutine update(array1,array2)
implicit none
!DEC$ ATTRIBUTES DLLEXPORT, C, ALIAS:'update'::update
real*8,dimension(1000) :: array1 ! fixed-length array, data from HAWC2 to DLL
! - in this case with length 1000
real*8,dimension(100)  :: array2 ! fixed-length array, data from DLL to HAWC2
! - in this case with length 100

! Code is written here

end subroutine initialize
```

# Wind and turbulence

## Main command block -wind

Obl.	Command name	Explanation
*	wsp	1. Mean wind speed in center [m/s]
*	density	1. Density of the wind [kg/m <sup>3</sup> ]
*	tint	Turbulence intensity [-].
*	horizontal_input	This command determines whether the commands above should be understood as defined in the global coordinate system (with horizontal axes) or the meteorological coordinates system (u,v,w) witch can be tilted etc. 1. (0=meteorological – default, 1=horizontal)
*	center_pos0	Global coordinates for the center start point of the turbulence box, meteorological coordinate system etc. (default should the hub center) 1. x <sub>G</sub> [m] 2. y <sub>G</sub> [m] 3. z <sub>G</sub> [m]
*	windfield_rotations	Orientation of the wind field. The rotations of the field are performed as a series of 3 rotations in the order yaw, tilt and roll. When all angles are zero the flow direction is identical to the global y direction. 1. Wind yaw angle [deg], positive when the wind comes from the right, seen from the turbine looking in the -y <sub>G</sub> direction. 2. Terrain slope angle [deg], positive when the wind comes from below. 3. Roll of wind field [deg], positive when the wind field is rotated according to the turbulence u-component.
*	shear_format	Definition of the mean wind shear 1. Shear type 0=none. !This option sets the mean wind speed to zero ! $\bar{u}(z) = 0$ 1=constant $\bar{u}(z) = c$ , 2=logarithmic $\bar{u}(z) = u_0 \frac{\log \frac{-z_0^G + z^M}{r_0}}{\log \frac{-z_0^G}{r_0}}$ 3=power law $\bar{u}(z) = u_0 \left( \frac{-z_0^G + z^M}{-z_0^G} \right)^\alpha$ 4=linear $\bar{u}(z) = u_0 \frac{\partial u}{\partial z}$ 2. Parameter used together with shear type (case of shear type: 0=dummy, 1=c, 2=r <sub>0</sub> , 3= α, 4=du/dz at center)
*	turb_format	1. Turbulence format (0=none, 1=mann, 2=flex)

Obl.	Command name	Explanation
*	tower_shadow_method	<ol style="list-style-type: none"> <li>1. Tower shadow model (0=none, 1=potential flow – default, 2=jet model, 3=potential_2 (flow where shadow source is moved and rotated with tower coordinates system). Please see section, page 61 for sub block commands.</li> </ol>
	scale_time_start	<ol style="list-style-type: none"> <li>1. Starting time for turbulence scaling [s]. Stop time is determined by simulation length.</li> </ol>
	wind_ramp_factor	<p>Command that can be repeated as many times as needed.</p> <p>The wind_ramp_factor is used to calculate a factor that is multiplied to the wind speed vectors. Can be used to make troublefree cut-in situations. Linear interpolation is performed between <math>t_0</math> and <math>t_{stop}</math>.</p> <ol style="list-style-type: none"> <li>1. time start, <math>t_0</math></li> <li>2. time stop, <math>t_{stop}</math></li> <li>3. factor at <math>t_0</math></li> <li>4. factor at <math>t_{stop}</math></li> </ol>
	wind_ramp_abs	<p>Command that can be repeated as many times as needed.</p> <p>The wind_ramp_abs is used to calculate a wind speed that is added to the wind speed u-component. Can be used to make wind steps etc. Linear interpolation is performed between <math>t_0</math> and <math>t_{stop}</math>.</p> <ol style="list-style-type: none"> <li>1. time start, <math>t_0</math></li> <li>2. time stop, <math>t_{stop}</math></li> <li>3. wind speed at <math>t_0</math></li> <li>4. wind speed at <math>t_{stop}</math></li> </ol>
	user_defined_shear	<ol style="list-style-type: none"> <li>1. Filename incl. relative path to file containing user defined shear factors (example ./data/shear.dat)</li> </ol>
	user_defined_shear_turbulence	<ol style="list-style-type: none"> <li>1. Filename incl. relative path to file containing user defined shear turbulence factors (example ./data/shearturb.dat)</li> </ol>

Obl.	Command name	Explanation
	iec_gust	<p>Gust generator according to IEC 61400-1</p> <ol style="list-style-type: none"> <li> <p>Gust type</p> <p>‘eog’ = extreme operating gust  <math>u(z,t) = u(z,t) - 0.37A \sin\left(\frac{3\pi(t-t_0)}{T}\right) \left(1 - \cos\frac{2\pi(t-t_0)}{T}\right)</math></p> <p>‘edc’ = extreme direction change  <math>\theta(t) = 0.5\varphi_0 \left(1 - \cos\left(\frac{\pi(t-t_0)}{T}\right)\right)</math></p> <p>‘ecg’ = extreme coherent gust  <math>u(z,t) = u(z,t) + 0.5A \left(1 - \cos\left(\frac{\pi(t-t_0)}{T}\right)\right)</math></p> <p>‘ecd’ = extreme coherent gust with dir. change  <math>u(z,t) = u(z,t) + 0.5A \left(1 - \cos\left(\frac{\pi(t-t_0)}{T}\right)\right)</math>  <math>\theta(t) = 0.5\varphi_0 \left(1 - \cos\left(\frac{\pi(t-t_0)}{T}\right)\right)</math></p> <p>‘ews’ = extreme wind shear  <math>d = \sqrt{y_M^2 + z_M^2}</math>  <math>u(z,t) = u(z,t) + dA \left(1 - \cos\left(\frac{2\pi(t-t_0)}{T}\right)\right) \cos\left(\arctan 2(y^M, -z^M) - \varphi_0\right)</math></p> <p>even though the ‘ews’ expressions do not match the expressions in the standard completely, it gives identical results provided a mutual power law shear is used and the A parameter is set to</p> <math display="block">A = \frac{2.5 + 0.2\beta\sigma_1 \left(\frac{D}{\lambda_1}\right)^{\frac{1}{2}}}{D}</math> <p>and the parameter <math>\varphi_0</math> is set to 0, 90, 180, 270 [deg] respectively.</p> </li> <li> <p>Amplitude A [m/s]. For the ‘eog’, ‘edc’, ‘ecd’ this corresponds to the parameter ‘V<sub>gust</sub>’, ‘0’, ‘V<sub>cg</sub>’ respectively, in the IEC61400-1 standard.</p> </li> <li> <p>Angle <math>\varphi_0</math> [deg]</p> </li> <li> <p>Time start, <math>t_0</math> [s]</p> </li> <li> <p>Duration T [s]</p> </li> </ol>

## Sub command block - mann

Block that must be included if the mann turbulence format is chosen. Normal practice is to use all three turbulence components (u,v,w) but only the specified components are used. In 2008 the turbulence generator was linked to the code so mannturbulence can be created without using external software. The command create\_turb\_parameters will search for turbulence files with names given below, but if these are not found the turbulence will be created.

A short explanation of the parameters  $L$  and  $\alpha\varepsilon^{2/3}$  and its relation to the IEC61400-1 ed. 3 standard is given:

The fundamentals of the Mann model is isotropic turbulence in neutral atmospheric conditions. The energy spectrum is given based on the Von Karman spectrum (1). In isotropic turbulence, the properties of turbulence like variance and turbulent length scale is identical for all three direction corresponding to vortex structures being circular.

$$E(k) = \alpha\varepsilon^{\frac{2}{3}} L^{\frac{5}{3}} \frac{(Lk)^4}{(1 + (Lk)^2)^{\frac{17}{6}}} \quad (1)$$

The relation between wave number  $k$  and frequency  $f$  is related through the mean wind speed  $\bar{U}$ .

$$k = \frac{2\pi f}{\bar{U}} \quad (2)$$

However, atmospheric conditions are not isotropic and the vortex structures become more elliptic in shape with longer length scale and higher variance level in the  $u$  direction. In the Mann model, this is accounted for using rapid distortion theory quantified through a shear blocking factor  $\Gamma$ . A  $\Gamma$  parameter of 0 corresponds to isotropic turbulence, whereas a higher  $\Gamma$  value is used for non-isotropic turbulence. The relation between non-isotropic and isotropic properties as function of  $\Gamma$  can be seen in Figure 4. It is normally recommended to use  $\Gamma = 3.9$  for normal atmospheric conditions. A length scale of  $L = 0.7\Lambda_1$  is recommended for normal conditions.  $\Lambda_1$  is defined as the wavelength where the longitudinal power spectral density is equal to 0.05. According to the IEC61400-1 the wavelength  $\Lambda_1$  shall be considered as a constant of 42m (above a height of 60m).

In the Mann generation of turbulence a length scale  $L$  has to be used. This is the length scale of the Von Karman spectrum (1) and therefore different than the length scale used in the Kaimal formulation (3). The energy spectrum of Kaimal is formulated

$$E(f) = \sigma^2 \frac{4L/\bar{U}}{(1 + 6fL/\bar{U})^5} \quad (3)$$

where the input parameters are given based on the table values in

	Velocity component index ( $k$ )		
	1	2	3
Standard deviation $\sigma_k$	$\sigma_1$	$0,8 \sigma_1$	$0,5 \sigma_1$
Integral scale, $L_k$	$8,1 \Lambda_1$	$2,7 \Lambda_1$	$0,66 \Lambda_1$

Table 3: Information about Kaimal length scales and standard deviation ratio from the IEC61400-1

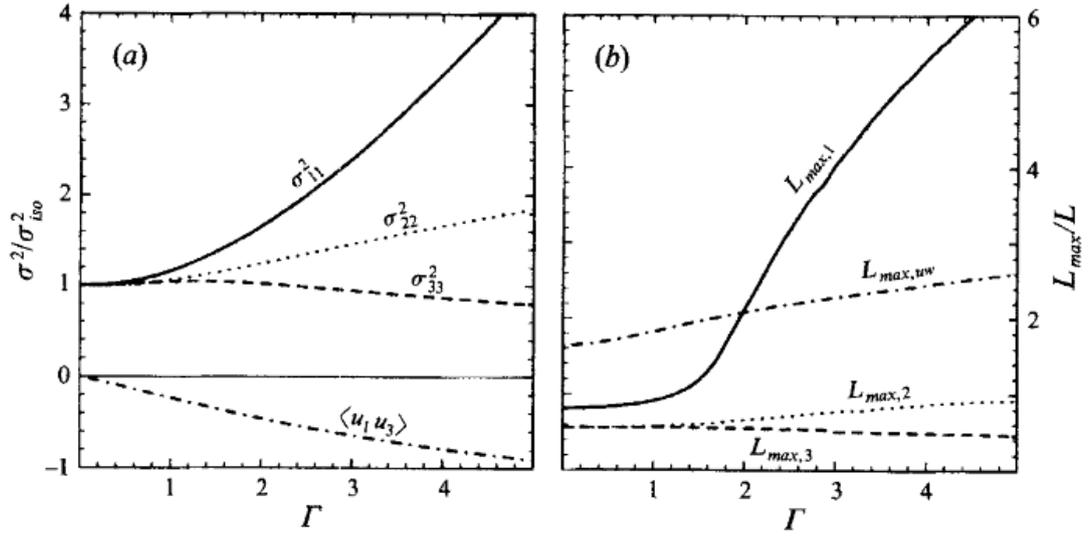


Figure 4: Turbulence characteristics compared to isotropic conditions as function of gamma parameter, Mann.. Left: Relation between variance is changed for higher shear distortions. Right: The relation between length scales are also changed for non-isotropic turbulence. It is recommended to use  $\Gamma = 3.9$  for normal atmospheric conditions. This is also the requirement in the IEC61400-1 standard. Isotropic conditions are obtained using  $\Gamma = 0$ .

The result of using  $\Gamma = 3.9$  is that the structure of the turbulence corresponds to the normal atmospheric conditions, but the actual level of turbulence is also affected as seen in Figure 4. It is not straight forward to give the exact analytical relationship between the input parameter  $\alpha\varepsilon^{\frac{2}{3}}$  and the final longitudinal variance and it is therefore very practical to introduce a turbulence scaling factor SF. This turbulence scaling factor is calculated based on the actual variance level in the box (normally extracted in the center of the box of longitudinal turbulence) and the target variance  $\sigma_{\text{target}}^2$  based on the requested turbulence intensity  $\sigma = Ti \bar{U}$ . In this case of rescaling, which is the normal usage, the input value for  $\alpha\varepsilon^{\frac{2}{3}}$  can be any arbitrary value except for zero.

$$SF = \sqrt{\frac{\sigma_{\text{target}}^2}{\sigma^2}} \quad (4)$$

The scale factor is to be multiplied to every values in the turbulence box for all the u,v and w directions. This is done automatically inside HAWC2.

Obl.	Command name	Explanation
	create_turb_parameters	<p>With this command, the code will search for turbulence files with names given below, but if these are not found the turbulence will be created based on the given parameters.</p> <ol style="list-style-type: none"> <li>1. Length scale L (normally L=29.4)</li> <li>2. <math>\alpha\varepsilon^{\frac{2}{3}}</math> (when rescaling applied, 1.0 is normal practice)</li> <li>3. <math>\gamma</math> (3.9 for neutral atmospheric conditions)</li> <li>4. Seed number (any integer will do)</li> <li>5. High frequency compensation (1=point velocity)</li> </ol>

Obl.	Command name	Explanation
		only represent local value which is closest to anemometer measurements, recommended in most cases, 0=point velocity represents average velocity in grid volume)
	filename_u	1. Filename incl. relative path to file containing mann turbulence u-component (example ./turb/mann-u.bin)
	filename_v	1. Filename incl. relative path to file containing mann turbulence v-component (example ./turb/mann-v.bin)
	filename_w	1. Filename incl. relative path to file containing mann turbulence w-component (example ./turb/mann-w.bin)
*	box_dim_u	1. Number of grid points in u-direction 2. Length between grid points in u-direction [m]
*	box_dim_v	1. Number of grid points in v-direction 2. Length between grid points in v-direction [m]
*	box_dim_w	1. Number of grid points in w-direction 2. Length between grid points in w-direction [m]
	std_scaling	Ratio between standard deviation for specified component related to turbulence intensity input specified in main wind command block. If the std_scaling command is omitted, the SF is determined based on the u-variance, the SF for v and w direction are kept equal to u-direction (recommended) 1. Ratio to u-direction (default=1.0) 2. Ratio to v-direction (default=0.8) 3. Ratio to w-direction (default=0.5)
	dont_scale	If this command is used the normal scaling to ensure the specified turbulence intensity is bypassed. 1. (0=scaling according to specified inputs – default, 1=raw turbulence field used without any scaling)

### Sub command block - flex

Block that must be included if the flex turbulence format is chosen.

Obl.	Command name	Explanation
*	filename_u	1. Filename incl. relative path to file containing flex turbulence u-component (example ./turb/flex-u.int)
*	filename_v	1. Filename incl. relative path to file containing flex turbulence v-component (example ./turb/flex-v.int)
*	filename_w	1. Filename incl. relative path to file containing flex turbulence w-component (example ./turb/flex-w.int)
	std_scaling	Ratio between standard deviation for specified component related to turbulence intensity input specified in main wind command block. 1. Ratio to u-direction (default=1.0) 2. Ratio to v-direction (default=0.7) 3. Ratio to w-direction (default=0.5)

## File description of a user defined shear

In this file a user defined shear used instead, or in combination with one of the default shear types (logarithmic, exponential...). When the user defined shear is used the name and location of the datafile must be specified with the *wind – user\_defined\_shear* command. This command specifies the location of the file and activates the user defined shear. If this shear is replacing the original default shear the command *wind – shear\_format* must be set to zero!

Only one shear can be present in a single file. The shear describes the mean wind profile of the u, v and w component of a vertical cross section at the rotor. The wind speeds are normalized with the mean wind speed defined with the command *wind – wsp*.

Line number	Description
1	Headline (not used by HAWC2)
2	Information of shear v-component. #1 is the number of columns, NC #2 is the number of rows, NR
3	Headline (not used by HAWC2)
4..+NR	Wind speed in v-direction, normalized with u-mean. # NC columns
+1	Headline (not used by HAWC2)
+1..+NR	Wind speed in u-direction, normalized with u-mean. # NC columns.
+1	Headline (not used by HAWC2)
+1..+NR	Wind speed in w-direction, normalized with u-mean. # NC columns
+1	Headline (not used by HAWC2)
+1..+NC	Horizontal position of grid points (meteorological coo)
+1	Headline (not used by HAWC2)
+1..+NR	Vertical position of grid points (meteorological coo)

## Example of user defined shear file

```
# User defined shear file
3 4 # nr_v, nr_w      array sizes
# shear_v component, normalized with U_mean
0.0 0.0 0.0
0.0 0.0 0.0
0.0 0.0 0.0
0.0 0.0 0.0
# shear_u component, normalized with U_mean
1.0 1.0 1.0
1.0 1.0 1.0
1.0 1.0 1.0
1.0 1.0 1.0
# shear_w component, normalized with U_mean
0.0 0.0 0.0
0.0 0.0 0.0
0.0 0.0 0.0
0.0 0.0 0.0
# v coordinates
-50.0
0.0
50.0
# w coordinates (zero is at ground level)
0.0
60.0
100.0
200.0
```

## Sub command block - wakes

Block that must be included if the Dynamic Wake Meandering model is used to model the wind flow from one or more upstream turbines.

In order to make the model function, two Mann turbulence boxes must be used. One for the meandering turbulence – which is a box containing atmospheric turbulence, but generated with a coarse resolution in the v,w plane (grid size of 1 rotor diameter). It is important that the turbulence vectors at the individual grid points represent a mean value covering a grid cube. It is also important that the total size of the box is large enough to cover the different wake sources including their meandering path. The resolution in the u-direction should be as fine as possible. The used length scale should correspond to normal turbulence condition. The other turbulence box that is needed is a box representing the micro scale turbulence from the wake of the upstream turbine itself. The resolution of this box should be fine (e.g. 128x128 points) in the v,w plane which should only cover 1 rotor diameter. The resolution in the u direction should also be fine, but a short length of the box (e.g. 2.5Diameter) is OK, since the turbulence box is reused. The length scale for this turbulence is significantly shorter than for the other boxes since it represents turbulence from tip and root vortices mainly. A length scale of 1/16 rotor diameter seems appropriate.

The two turbulence boxes are included by the following sub commands

```
begin mann_meanderturb;  
    (parameters are identical to the normal Mann turbulence box, see above)  
end mann_meanderturb;  
  
begin mann_microturb;  
    (parameters are identical to the normal Mann turbulence box, see above)  
end mann_microturb;
```

The rest of the wake commands are given in the following table.

Obl.	Command name	Explanation
*	nsource	1. Number of wake sources. If 0 is used the wake module is by-passed (no source positions can be given in this case).
*	source_pos	Command that must be repeated <i>nsource</i> times. This gives the position of the wake source (hub position) in global coordinates. Wake source position given for down stream turbines are however not used in the simulations since they don't affect the target turbine. 1. x-pos [m] 2. y-pos [m] 3. z-pos [m]
*	op_data	Operational conditions for the wake sources. 1. Rotational speed [rad/s] 2. Collective pitch angle [deg]. Defined positive according to the blade root coo, with z-axis from root towards tip.
	ble_parameters	Parameters used for the BLE model used for developing the wake deficit due to turbulent mixing. 1. $k_1$ [-], default=0.10 2. $k_2$ [-], default=0.008 3. clean-up parameter (0=intermediate files are kept, 1=intermediate files are deleted), default=1
	microturb_factors	Parameters used for scaling the added wake turbulence according to the deficit depth and depth derivative. 1. $k_{m1}$ [-], factor on deficit depth, default=0.60 2. $k_{m2}$ [-], factor on depth derivative, default=0.25
	multiple_deficit_method	Command that is used for choosing the best approach for handling multiple deficit 1. method (1=MAX operator (default), 2=Direct summation) In general it is recommende to use the MAX operator when the ambient free wind speed is below rated and the direct summation approach above rated wind speed.
	tint_meander	Turbulence intensity of the meander turbulence box. If this command is not used then the default turbulence intensity from the general wind commands is used (normal use) 1. Turbulence intensity [-]
	use_specific_deficit_file	File with the deficits used in the correct downstream distance is used instead of the build in deficit generator. The windspeed deficits are non-dim with the mean wind speed. 1. Filename incl. path (e.g. ./data/deficit.data)
	write_ct_cq_file	File including the local axial and tangential forces (non-dim) as function of blade radius is written. 1. Filename incl. path (e.g. ./res/ct_cq.data)
	write_final_deficits	File with the deficits used in the correct downstream distance is written. The windspeed deficits are non-dim with the mean wind speed. 1. Filename incl. path (e.g. ./res/ct_cq.data)

### File description of a user defined wake deficit file

When another flow solve has been used to find the non-dim turbulence deficit, eg. using an actuator disc approach, this can replace the deficit otherwise calculated internally. This method cannot be used together with multiple deficits as only one deficit can be read.

Line number	Description
1	#1 is a char (not used). Can eg be a '#' #2 is the number of rows, NR
2..+NR	Deficit non-dim with ambient free mean wind speed. #1 Radius (non-dim with rotor radius) #2 Deficit (non-dim with free mean wind speed). In the free

### Example of user defined wake deficit file

```
#      121
0.000000000E+00      8.276891200E-01
2.500000000E-02      8.486243600E-01
5.000000000E-02      8.809613720E-01
7.500000000E-02      9.007844070E-01
1.000000000E-01      8.957724550E-01
1.250000000E-01      8.660702830E-01
1.500000000E-01      8.303410890E-01
1.750000000E-01      8.044380440E-01
2.000000000E-01      7.895593800E-01
2.250000000E-01      7.786515560E-01
2.500000000E-01      7.691674220E-01
2.750000000E-01      7.618372330E-01
3.000000000E-01      7.572012850E-01
3.250000000E-01      7.550918200E-01
3.500000000E-01      7.542137030E-01
3.750000000E-01      7.518827010E-01
4.000000000E-01      7.456746090E-01
4.250000000E-01      7.357259740E-01
4.500000000E-01      7.250309980E-01
4.750000000E-01      7.168460970E-01
5.000000000E-01      7.119492260E-01
5.250000000E-01      7.088296670E-01
5.500000000E-01      7.057605130E-01
5.750000000E-01      7.021459650E-01
6.000000000E-01      6.983228280E-01
6.250000000E-01      6.947171830E-01
6.500000000E-01      6.913423360E-01
6.750000000E-01      6.879199230E-01
7.000000000E-01      6.842943230E-01
7.250000000E-01      6.806519720E-01
7.500000000E-01      6.773263690E-01
7.750000000E-01      6.744196220E-01
8.000000000E-01      6.716445590E-01
8.250000000E-01      6.684818930E-01
8.500000000E-01      6.644046880E-01
8.750000000E-01      6.592242170E-01
9.000000000E-01      6.529686490E-01
9.250000000E-01      6.445576730E-01
9.500000000E-01      6.324201240E-01
9.750000000E-01      6.173566910E-01
1.000000000E+00      5.982423590E-01
1.028634580E+00      5.679249380E-01
1.058116050E+00      5.982195030E-01
1.088469450E+00      7.292761710E-01
1.119720570E+00      9.095984580E-01
1.151895960E+00      1.014958390E+00
1.185022960E+00      1.022114240E+00
1.219129700E+00      1.017341600E+00
...
8.903031630E+00      1.000285950E+00
9.165402860E+00      1.000213540E+00
9.435533870E+00      1.000143160E+00
9.713654150E+00      1.000066170E+00
1.000000000E+01      1.000018010E+00
```

### Sub command block – tower\_shadow\_potential

Block that must be included if the potential flow tower shadow model is chosen.

Obl.	Command name	Explanation
*	tower_offset	The tower shadow has its source at the global coordinate z axis. The offset is the base point for section 1

		1. Offset value (default=0.0)
*	nsec	Command that needs to present before the radius commands. 1. Number of datasets specified by the radius command.
*	radius	Command that needs to be listed nsec times. 1. z coordinate [m] 2. Tower radius at z coordinate [m]

### Sub command block – tower\_shadow\_jet

Block that must be included if the model based on the boundary layer equations for a jet is chosen. This model is especially suited for downwind simulations.

Obl.	Command name	Explanation
*	tower_offset	The tower shadow has its source at the global coordinate z axis. The offset is the base point for section 1 1. Offset value (default=0.0)
*	nsec	Command that needs to present before the radius commands. 1. Number of datasets specified by the radius command.
*	radius	Command that needs to be listed nsec times. 1. z coordinate [m] 2. Tower radius at z coordinate [m] 3. $C_d$ drag coefficient of tower section (normally 1.0 for circular section, but this depends heavily on the reynold number)

### Sub command block – tower\_shadow\_potential\_2

Block that must be included if the tower shadow method 3 is chosen. This potential model is principally similar to the potential flow model described previously but differs in the way that the shadow source is moved and rotated in space as the tower coordinate system is moving and rotating. It is also possible to define several tower sources e.g. if the tower is a kind of tripod or quattropod. Just include more tower\_shadow\_potential\_2 blocks if more sources are required.

The coordinate system that the shadow method is linked to is specified by the user, e.g. the mbdy coordinate from the tower main body. To make sure that the tower source model is always linked in the same way as the tower (could be tricky since the tower is fully free to be specified along the x,y or z axis or a combination) the base coordinate system for the shadow model is identical to the coordinates system obtained by the local element coordinates, where the z axis is always pointing from node 1 towards node 2. This is the reason that the tower radius input has to specified with positive z-values, see below.

Obl.	Command name	Explanation
*	tower_mbdy_link	Name of the main body to which the shadow source is linked. 1. mbdy name
*	nsec	Command that needs to present before the radius commands. 1. Number of datasets specified by the radius command.
*	radius	Command that needs to be listed nsec times. 1. z coordinate [m] (allways positive!) 2. Tower radius at z coordinate [m]

## Sub command block – tower\_shadow\_jet\_2

Block that must be included if the tower shadow method 4 is chosen. This jet model is principally similar to the jet model described previously but differs in the way that the shadow source is moved and rotated in space as the tower coordinate system is moving and rotating. It is also possible to define several tower sources e.g. if the tower is a kind of tripod or quattropod. Just include more tower\_shadow\_jet\_2 blocks if more sources are required.

The coordinate system that the shadow method is linked to is specified by the user, e.g. the mbdy coordinate from the tower main body. To make sure that the tower source model is always linked in the same way as the tower (could be tricky since the tower is fully free to be specified along the x,y or z axis or a combination) the base coordinate system for the shadow model is identical to the coordinates system obtained by the local element coordinates, where the z axis is always pointing from node 1 towards node 2. This is the reason that the tower radius input has to specified with positive z-values, see below.

Obl.	Command name	Explanation
*	tower_mbdy_link	Name of the main body to which the shadow source is linked. 1. mbdy name
*	nsec	Command that needs to present before the radius commands. 1. Number of datasets specified by the radius command.
*	radius	Command that needs to be listed nsec times. 1. z coordinate [m] (allways positive!) 2. Tower radius at z coordinate [m]
*	radius	Command that needs to be listed nsec times. 1. z coordinate [m] 2. Tower radius at z coordinate [m] 3. $C_d$ drag coefficient of tower section (normally 1.0 for circular section, but this depends heavily on the reynold number)

## Sub command block – turb\_export

With this sub command block, a mann format turbulence box including information from shear, wakes, tower shadow etc. is written. Same data point positions are used as specified in the turbulence module including the parameters specified for the originally used mann turbulence box.

Obl.	Command name	Explanation
*	filename_u	Filename of turbulence box with axial turbulence 1. File name
*	filename_v	Filename of turbulence box with lateral turbulence 1. File name
*	filename_w	Filename of turbulence box with vertical turbulence 1. File name

# Aerodynamics

## Main command block - aero

This module set up parameters for the aerodynamic specification of the rotor. It is also possible to submit aerodynamic forces to other structures as example the tower or nacelle, but see chapter (Aerodrag) regarding this. The module can be added as many times as requested if multiple aerodynamic rotors are needed.

Obl.	Command name	Explanation
	name	Name o rotor (in case of multiple rotors defined)
*	nblades	Must be the first line in aero commands! 1. Number of blades
*	hub_vec	Link to main-body vector that points downwind from the rotor under normal conditions. This corresponds to the direction from the pressure side of the rotor towards the suction side where the coordinate system is normally taken from the main shaft system.. 1. mbdy name or 'old_input' if old_htc_structure format is applied. 2. mbdy coo. component (1=x, 2=y, 3=z). If negative the opposite direction used. Not used together with old_htc_structure input (specify a dummy number). 3. Node number (optional). Node number on mbdy where rotor center is located. 'last' can also be used (default if no value is present).
*	link	Linker between structural blades and aerodynamic blades. There must be same number of link commands as nblades! 1. blade number 2. link chooser – options are <ul style="list-style-type: none"> <li>• mbdy_c2_def (used with new structure format)</li> <li>• blade_c2_def (used with old structure format, see description below in this chapter)</li> </ul> 3. mbdy name (with new structure format), not used to anything with old structure format.
*	ae_filename	1. Filename incl. relative path to file containing aerodynamic layout data (example ./data/hawc2_ae.dat)
*	pc_filename	1. Filename incl. relative path to file containing profile coefficients (example ./data/hawc2_pc.dat)
*	induction_method	1. Choice between which induction method that shall be used (0=none, 1=normal BEM dynamic induction, 2= Near Wake induction method)
*	aerocalc_method	1. Choice between which aerodynamic load calculation method that shall be used. (0=none, 1=normal)
	aerosections	Number of aerodynamic calculation points at a blade. The distribution is performed automatically using a cosinus transformation which gives closest spacing at root and tip. 1. Number of points at each blade.
	aero_distribution	1. Distribution method of aerodynamic

Obl.	Command name	Explanation
	name	Name of rotor (in case of multiple rotors defined)
		<p>calculation points. Options are:</p> <ul style="list-style-type: none"> <li>• “default” number. The distribution is performed automatically using npoints position with a cosine transformation which gives closest spacing at root and tip.</li> <li>• “ae_file” set. The distribution is given with same spacing as values in the ae_file with set number set..</li> </ul>
*	ae_sets	<p>Set number from ae_filename that is linked to blade 1,2,...,nblades</p> <ol style="list-style-type: none"> <li>1. set for blade number 1</li> <li>2. set for blade number 2</li> <li>.</li> <li>.</li> <li>.</li> <li>nblades. set for blade number nblades</li> </ol>
*	tiploss_method	<ol style="list-style-type: none"> <li>1. Choice between which tip-loss model that shall be used (0=none, 1=prandtl (default))</li> </ol>
*	dynstall_method	<ol style="list-style-type: none"> <li>1. Choice between which dynamic stall model that shall be used (0=none, 1=Stig Øye method, 2=MHH Beddoes method, 3=Gaunaa-Andersen method with Deformable Trailing Edge Flap’s)</li> </ol>
	3d_correct_method	<p>Airfoil Cl values from the pc_file is modified for 3D effects.</p> <ol style="list-style-type: none"> <li>1. Correction method (1=Snel method for correction of C<sub>l</sub> values)</li> </ol>
	external_bladedata_dll	<p>Blade structural data are found in an external encrypted dll. If this command is present the following command lines shall not be present (ae_filename, pc_filename and ae_sets).</p> <ol style="list-style-type: none"> <li>1. Company name (that has been granted a password, eg. dtu).</li> <li>2. Password for opening this specific dll, eg. test1234</li> <li>3. path and filename for the dll. eg. ./data/encr_blade_data.dll</li> </ol>
	output_profile_coef_filename	<p>Interpolated profile coefficients at all aerodynamic calculation points are written into a data file. This command can not be used in combination with encrypted_profile_coef_filename.</p> <ol style="list-style-type: none"> <li>1. path and filename for the dll. eg. ./res/aero_profiles.dat</li> </ol>

### Sub command block – dynstall\_so

Block that may be included if the Stig Øye dynamic stall method is chosen. If not included default parameters are automatically used.

Obl.	Command name	Explanation
	dclda	<ol style="list-style-type: none"> <li>1. Linear slope coefficient for unseparated flow (default=6.28)</li> </ol>
	dcldas	<ol style="list-style-type: none"> <li>1. Linear slope coefficient for fully separated flow (default=3.14)</li> </ol>
	alfs	<ol style="list-style-type: none"> <li>1. Angle of attack [deg] where profile flow is fully separated. (default=40)</li> </ol>
	alrund	<ol style="list-style-type: none"> <li>1. Factor used to generate synthetic separated flow Cl values (default=40)</li> </ol>

	taufak	1. Time constant factor in first order filter for F function (default=10.0). Internally used as $\tau = \text{taufak} * \text{chord} * \text{vrel}$
--	--------	---

### Sub command block – dynstall\_mhh

Block that may be included if the MHH Beddoes dynamic stall method is chosen (see Risø report 1354(en)). If not included defaults parameters are automatically used.

Obl.	Command name	Explanation
	a1	1. Coefficients of the exponential potential flow step response approximation: $\Phi(s) = 1 - A1 * \exp(-b1*s) - A2 * \exp(-b2*s)$ . (default= 0.165)
	a2	1. Coefficients of the exponential potential flow step response approximation: $\Phi(s) = 1 - A1 * \exp(-b1*s) - A2 * \exp(-b2*s)$ . (default= 0.335)
	b1	1. Coefficients of the exponential potential flow step response approximation: $\Phi(s) = 1 - A1 * \exp(-b1*s) - A2 * \exp(-b2*s)$ . (default= 0.0455)
	b2	1. Coefficients of the exponential potential flow step response approximation: $\Phi(s) = 1 - A1 * \exp(-b1*s) - A2 * \exp(-b2*s)$ . (default= b2=0.300)
	update	Choice between update methods: 1. 1 (default)=>update aerodynamics all iterations all timesteps; 0=>only update aerodynamics first iteration each new timestep
	taupre	1. Non-dimensional time-lag parameters modeling pressure time-lag. Default value =1.5
	taubly	1. Non-dimensional time-lag parameters modeling boundary layer time-lag. Default value=6.0
	only_potential_model	1. 0(default)=>run full MHH beddoes model; 1=>Potential flow model dynamics superposed to steady force coefficients;

### Sub command block – dynstall\_ateflap

This sub-block should be included if the ATEFlap dynamic stall model is chosen (*dynstall\_method* number 3). The dynamic stall model is similar to the MHH model, expanded to account for steady and dynamic effects of trailing edge flap deflections; the model is described in L. Bergami and M. Gaunaa, *ATEFlap Aerodynamic model, a dynamic stall model including the effects of trailing edge flap deflection* (Risoe-R-1792(EN), Risoe DTU, February 2012).

The model requires a .ds input file containing pre-processed steady aerodynamic data for the blade sections containing a flap (see following paragraphs for the file specifications). Sections without any flap are attributed steady input data according to the aerodynamic layout specified in the *ae\_filename*.

Obl.	Command name	Explanation
------	--------------	-------------

Obl.	Command name	Explanation
*	flap	Mandatory command to define a flap section. The flap is defined on all the blades of the rotor. Command syntax: <ol style="list-style-type: none"> <li>1. Radius <math>r_{start}</math> [in m]. Starting point of flap section.</li> <li>2. Radius <math>r_{end}</math> [in m]. Ending point of flap section (should be <math>&gt; r_{start}</math>).</li> <li>3. Filename incl. relative path to .ds file containing pre-processed aerodynamic steady input data. See <i>.ds file</i> specifications in the following paragraph.</li> </ol> N.B. The location along the blade refer to the 'stretched' blade, distances are given along the half-chord line (as the layout in <i>ae_file</i> ). A maximum of 99 flap sections can be defined.
	ais	Coefficients for the indicial response exponential function: <ol style="list-style-type: none"> <li>1. A1 (default= 0.1784)</li> <li>2. A2 (default=0.07549)</li> <li>3. A3 (default=0.3933)</li> </ol> Default coefficients describe the step response of a NACA 64-418 profile, where $t/c=0.18$ .
	bis	Coefficients of the exponential potential flow step response approximation: <ol style="list-style-type: none"> <li>1. B1 (default= 0.8000)</li> <li>2. B2 (default= 0.01815)</li> <li>3. B3 (default= 0.1390)</li> </ol> Default coefficients describe the step response of a NACA 64-418 profile, where $t/c=0.18$ .
	taupre	1. Non-dimensional time-lag parameters modelling pressure time-lag. Default value =1.5
	taubly	1. Non-dimensional time-lag parameters modelling boundary layer time-lag. Default value=6.0
	only_potential_model	1. 0(default)=>run full ATEFlap model; 1=>Potential flow model dynamics superposed to steady force coefficients;
	update	Choice between update methods: <ol style="list-style-type: none"> <li>1. 1 (default)=&gt;update aerodynamics all iterations all timesteps; 0=&gt;only update aerodynamics first iteration each new timestep</li> </ol>
	hystar	1. Camberline coef. (default= -4.675844E-003)
	fylestar	1. Camberline coef. (default= +4.155446E-004)
	fdydxle	1. Camberline coef. (default= +7.236104E-003)
	gdydxle	1. Camberline coef. (default= +3.309147E-003)

The camber line coefficients describe the camber line deformation shape induced by the flap; they are computed according to the thin-airfoil model described in Gaunaa's Wind Energy journal article *Unsteady two-dimensional potential-flow model for thin variable geometry airfoils*. Hystar and fylestar are dimensionless parameters corresponding to the shape integrals  $H_y$  and  $F_{yLE}$  normalized by the half-chord length. The default coefficients refer to a 10% chord length flap with a continuous deformation shape, describing a circular arc, whose chord forms an angle of 1 degree with the horizontal axis.

### Sub command block – bemwake\_method

Dynamic inflow settings used to calculate the dynamic induction. If not included defaults parameters are automatically used.

Obl.	Command name	Explanation
	nazi	1. Number of azimuthal points in the induction grid. A high number increased accuracy but slow down the simulation time. Default is 16.
	fw	Dynamic time constants and mixing ratio contribution for

		<p>the far wake part of the induction.</p> <ol style="list-style-type: none"> <li>1. Mixing ratio, default is 0.4</li> <li>2. k3 (poly. coef. for r/R sensitivity) default=0.0</li> <li>3. k2 (poly. coef. for r/R sensitivity) default=-0.4751</li> <li>4. k1 (poly. coef. for r/R sensitivity) default=0.4101</li> <li>5. k0 (poly. coef. for r/R sensitivity) default=1.921</li> </ol>
	nw	<p>Dynamic time constants and mixing ratio contribution for the near wake part of the induction.</p> <ol style="list-style-type: none"> <li>1. Mixing ratio, default is 0.6</li> <li>2. k3 (poly. coef. for r/R sensitivity) default=0.0</li> <li>3. k2 (poly. coef. for r/R sensitivity) default=-0.4783</li> <li>4. k1 (poly. coef. for r/R sensitivity) default=0.1025</li> <li>5. k0 (poly. coef. for r/R sensitivity) default=0.6125</li> </ol>
	a-ct-filename	Filename for a user defined relation bewteen a and ct.

## Data format for the aerodynamic layout

The format of this file which in the old HAWC code was known as the hawc\_ae file is changed slightly for the HAWC2 input format. The position of the aerodynamic center is no longer an input value, since the definition is that the center is located in  $C_{1/4}$  with calculated velocities in  $C_{3/4}$ .

Position of aerodynamic centers related to c2\_def section coo.

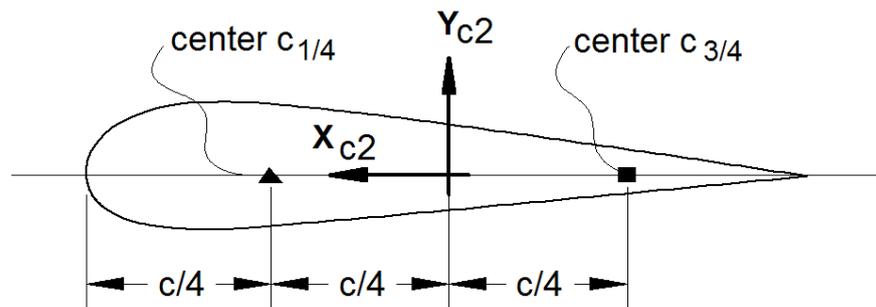


Figure 5: Illustration of aerodynamic centers  $c_{1/4}$  and  $c_{3/4}$

The format of the file is specified in the following two tables

Line number	Description
1	#1: Nset, Number of datasets present in the file. The format of each data set can be read below. The datasets are repeated without blank lines etc.
2	#1: Set number. #2: Nrows, Number of data rows for this set
3..2+Nrows	Data row according to Table 5

Table 4: Format of main data structure for the aerodynamic “\_ae” blade layout file

The content of the columns in a data row is specified in the table below.

Column	Parameter
1	r, distance from main_body node 1 along z-coordinate [m]
2	chord length [m]
3	thickness ratio between profile height and chord [%]
4	Profile coefficient set number
(5)	Optional column. When present, it includes a dynamic stall model selector. It is then possible to bypass or change dynamic stall model for different part of the blade. Numbers are identical to the one used in the command “aero dynstall_method”

Table 5 Format of the data rows for the aerodynamic “\_ae” blade layout file

## Example of an aerodynamic blade layout file

```

1      Number of datasets in the file.
1 25  Set nr, nrows.
0      2.42  100    1  Radius [m]  chord[m]      thick[%]      PC [-]
1.239  2.42  100    1
1.24   2.42  99.9   1
3.12   2.48  96.4   1
5.24   2.65  80.5   1
7.24   2.81  65.0   1
9.24   2.98  51.6   1
11.24  3.14  40.3   1
13.24  3.17  32.5   1
15.24  2.99  28.4   1
17.24  2.79  25.6   1
19.24  2.58  23.7   1
20.44  2.46  22.8   1
23.24  2.21  20.9   1
25.24  2.06  20.0   1
27.24  1.92  19.4   1
29.24  1.8   19.0   1
31.24  1.68  18.7   1
33.24  1.55  18.6   1
35.24  1.41  18.3   1
37.24  1.18  17.9   1
38.24  0.98  17.3   1
39.24  0.62  16.3   1
39.64  0.48  15.7   1
40.00  0.07  14.8   1

```

### Data format for the profile coefficients file

The format of this file which in the old HAWC code was known as the hawc\_pc file has not been changed for the HAWC2 code.

The format of the file is specified in the following two tables

Line number	Description
1	#1: Nset, Number of datasets present in the file. The format of each data set can be read below. The datasets are repeated without blank lines etc.
2	#1: Nprofiles. Number of profiles included in the data set. There must be more than 1 Nprofiles. First profile is the thinnest, last profile is the thickest (continuously increasing order).
3	#1: Set number. #2: Nrows. #3: Thickness in percent of chord length
4..3+Nrows	Data row according to Table 7

Table 6: Format of main data structure for the profile coefficients file

The content of the columns in a data row is specified in table below.

Column	Parameter
1	$\alpha$ , angle of attack [deg]. Starting with -180.0, ending with +180.0
2	$C_l$ lift coefficient [-]
3	$C_d$ drag coefficient [-]
4	$C_m$ moment coefficient [-]

Table 7 Format of the data rows for the profile coefficients file

## Example of the profile coefficients file “\_pc file”

```

1 Airfoil data for the nrel 5 mw turbine
8
1 127 17 DU17 airfoil with an aspect ratio of 17. Original -180 to 180deg
-180.00 0.000 0.0198 0.0000
-175.00 0.374 0.0341 0.1880
-170.00 0.749 0.0955 0.3770
-160.00 0.659 0.2807 0.2747
-155.00 0.736 0.3919 0.3130
-150.00 0.783 0.5086 0.3428
-145.00 0.803 0.6267 0.3654
-140.00 0.798 0.7427 0.3820
-135.00 0.771 0.8537 0.3935
-130.00 0.724 0.9574 0.4007
-125.00 0.660 1.0519 0.4042
-120.00 0.581 1.1355 0.4047
-115.00 0.491 1.2070 0.4025
-110.00 0.390 1.2656 0.3981
-105.00 0.282 1.3104 0.3918
-100.00 0.169 1.3410 0.3838
-95.00 0.052 1.3572 0.3743
-90.00 -0.067 1.3587 0.3636
-85.00 -0.184 1.3456 0.3517
-80.00 -0.299 1.3181 0.3388
-75.00 -0.409 1.2765 0.3248
-70.00 -0.512 1.2212 0.3099
-65.00 -0.606 1.1532 0.2940
-60.00 -0.689 1.0731 0.2772
-55.00 -0.759 0.9822 0.2595

```

### Data format for the flap steady aerodynamic input (.ds file):

This file contains the pre-processed steady data required by the ATEFlap dynamic stall model. Steady lift, drag and moment coefficients are given as function of angle of attack and flap deflection, together with the fully separated and fully attached lift, and the separation function values required by the Beddoes-Leishmann dynamic stall model.

The input file can be generated automatically through an external pre-processing application, as for instance the “Preprocessor for ATEFlap Dynamic Stall Model, v.2.04”. Please refer to the application documentation for further details.

The format of the file is specified in the following two tables:

Line number	Description
1	Free for comments
2	Free for comments
3	#1: Aoa0 [rad]. Angle of attack returning a null steady lift
4	Free for comments
5	#1: dCl/dAoa [1/rad]. Gradient of the steady lift function with respect to angle of attack variations
6	Free for comments
7	#1: dCl/dBeta [-]. Gradient of the steady lift function with respect to flap deflection variations
8	Free for comments
9	#1: Nrows. Total number of the following data-rows.
10...9+Nrows	Data rows, as specified in following table.

Table 8: Format of main data structure for the .ds flap steady aerodynamic input file

The content of the columns in a data row is specified in table below.

Column	Parameter
1	$\alpha$ , Angle Of Attack [deg]. Starting with -180.0, ending with +180.0. External loop (changes value after going through all the beta flap deflection values, i.e. 100 rows)
2	Beta, flap deflection. Starting from -49 to +50. Internal loop (changes at every data row)
3	$C_{l\ st}$ . Steady lift coefficient [-]
4	$C_{l\ att}$ . Fully attached lift coefficient [-]
5	$C_{l\ fs}$ . Fully separated lift coefficient [-]
6	$C_d$ drag coefficient [-]
7	$C_m$ moment coefficient [-]
8	$f$ . Steady value of the separation function [-]

Table 9: Format of the data rows for the .ds flap steady aerodynamic input file

### Example of a .ds flap steady aerodynamic input file:

```

Input file for Flap dyn.stall model. Generated with Delphi preprocessor
.Linear Region: Aoa C10 [rad]:
-0.06523855
.Linear Region: dCl / dAoa [1/rad]:
6.60081861
.Linear Region: dCl / dBeta [1/deg]:
0.0435375
.Polars: 1.Aoa | 2.Beta | 3.Clst | 4.Cl Att | 5.Cl fs | 6.Cd | 7.Cm | 8.F
36100
-180 -49 -0.22013 -20.5241432 -0.22013 0.0199118108 0.0451649986 0
-180 -48 -0.22013 -20.5241432 -0.22013 0.0199118108 0.0451649986 0
...
-180 +50 0.21096 -20.088768 0.21096 0.0199443996 -0.0431930013 0
-179 -49 ...
-179 -48 ...
...
+180 +50 ...

```

### Data format for the user defined a-ct relation

The format of the file is specified in the following two tables

Line number	Description
1	Nset interpolationmethod. Nset is number of data row present in the file. The format of each data set can be read below. Interpolationmethod can either be "linear" or "akima"
2..Nset	Data row according to Table 7

Table 10: Format of main data structure for the profile coefficients file

The content of the columns in a data row is specified in table below.

Column	Parameter
1	non-dim radius r/R
2	k1 polynomium coef
3	k2 polynomium coef
4	k3 polynomium coef
5	k4 polynomium coef

Table 11 Format of the data rows for the profile coefficients file

### Main command block – blade\_c2\_def (for use with old\_htc\_structure format)

In this command block the definition of the centerline of the main\_body is described (position of the half chord). This command shall be used as a main command even though it is only used together with the aerodynamic module. The reason for this is that it used to submit information that is usually given in the new\_htc\_structure format, which is also a main command block. The input data given with the sec commands below is used to define a continuous differentiable line in space using akima spline functions. This centerline is used as basis for local coordinate system definitions for sections along the structure. If a straight line is requested a minimum of three points of this line must be present.

Obl.	Command name	Explanation
*	nsec	Must be the present before a “sec” command. 1. Number of section commands given below
*	sec	Command that must be repeated “nsec” times 1. Number 2. x-pos [m] 3. y-pos [m] 4. z-pos [m] 5. $\theta_z$ [deg]. Angle between local x-axis and main_body x-axis in the main_body x-y coordinate plane. For a straight blade this angle is the aerodynamic twist. Note that the sign is positive around the z-axis, which is opposite to traditional notation for etc. a pitch angle.

## Aerodrag (for tower and nacelle drag)

### Main command aerodrag

With this module it is possible to apply aerodynamic drag forces at a given number of structures.

### Subcommand aerodrag\_element

Command block that can be repeated as many times as needed. In this command block aerodynamic drag calculation points are set up for a given main body.

Obl.	Command name	Explanation
*	body_name mbdy_name	1. Main_body name to which the hydrodynamic calculation points are linked.
*	aerodrag_sections	1. Distribution method: ("uniform" only possibility) 2. Number of calculation points (min. 2).
	nsec	This command must be present before the sec commands 1. Number of sections given below
	sec	This command must be repeated nsec times 1. Distance in [m] along the main_body c2_def line. Positive directed from node 1 to node "last". 2. $C_d$ drag coefficient (default=1.0) 3. Width of structure (diameter)
	update_states	Logical parameter that determines whethe the movement of the structure is included or not. 1. parameter (1=states are updated (default), 0=not updated)

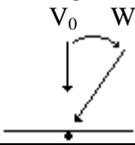
\*) Input commands that must be present

# Hydrodynamics

## Main command block - hydro

In this command block hydrodynamic forces calculated using Morison's formula is set up.

### Sub command block – water\_properties

Obl.	Command name	Explanation
*	gravity	1. Gravity acceleration (used for calculation of buoyancy forces). Default = 9.81 m/s <sup>2</sup>
*	mudlevel	1. Mud level [m] in global z coordinates.
*	mwl	1. Mean water level [m] in global z coordinates.
*	rho	1. Density of the water [kg/m <sup>3</sup> ]. Default=1027
	wave_direction	1. Wave direction [deg]. Direction is positive when the waves come forward from the right when looking towards the wind at default conditions. 
	current	1. Current type (0=none (default), 1=constant, 2=power law $U(z)=U0((z+mudlevel-mwl)/(mudlevel-mwl))^{\text{alfa}}$ ) 2. Current velocity at mwl, u0 3. type parameter. If type=2 then parameter is alfa 4. Current direction relative to wave direction [deg]. Positive direction if current comes from the right looking towards the incoming waves.
	water_kinematics_dll	1. Filename incl. relative path to file containing water kinematics dll (example ./hydro/water_kin.dll) 2. String sent to initialization of dll. This is typical the name of a local inputfile of the dll.

### Sub command block – hydro\_element

Command block that can be repeated as many times as needed. This command block set up hydrodynamic calculation points and link them to a main\_body.

Obl.	Command name	Explanation
*	body_name mbdy_name	1. Main_body name to which the hydrodynamic calculation points are linked.
*	hydrosections	1. Distribution method of hydrodynamic calculation points. Options are: <ul style="list-style-type: none"> <li>• “uniform” nnodes. Where uniform ensures equal distance of the calculation points. nnodes are number of calculation points.</li> <li>• “auto” nint. Here calculations points are chosen as the positions of the structural nodes and the hydro dynamic input section given by the sec command. The parameter <i>nint</i> is a refinement parameter given <i>nint</i> extra calculation points in between the other points.</li> </ul>

Obl.	Command name	Explanation
*	nsec	This command must be present before the sec commands 1. Number of sections given below
*	sec	This command must be repeated nsec times 1. Relative distance along the main_body c2_def line. Positive directed from node 1 to node "last". 2. $C_m$ inertia coefficient (default=1.0) 3. $C_d$ drag coefficient (default=1.0) 4. Cross sectional area [m <sup>2</sup> ] 5. Cross sectional area to which $C_m$ is related. (default=area for circular sections) [m <sup>2</sup> ] 6. Width of construction perpendicular to flow direction [m] 7. drdz gradient(optional). For calculating the buoyancy also for conical sections the gradient expressing the change in radius with change of distance along the main_body c2_def line. Only important when buoyancy forces are included. 8. Axial drag $C_d$ coefficient for concentrated force contribution (optional). Drag area is circular area defined by the local width. Contribution is quadratic regarding water velocity. 9. Axial inertia $C_m$ coefficient for concentrated force contribution (optional). Inertia volume is a sphere defined by the local width as diameter. 10. Axial drag $C_d$ coefficient for concentrated force contribution (optional). Drag area is circular area defined by the local width. Contribution is linear regarding water velocity. 11. Internal cross sectional area for flooded members [m <sup>2</sup> ] (optional). 0=member is not flooded. 12. Torque friction coefficient $C_f$ (optional). For rotating cylinders around local z-direction. $M_z = \frac{1}{16} \rho D^4 \omega^2 C_f$
	buoyancy	1. Specification whether buoyancy forces are included or not. 0=off (default), 1=on (remember to define the 7 <sup>th</sup> parameter in the sec input line).
	update_states	1. Specification whether the hydrodynamic sections are updated in time with respect to pos, vel, acc and orientations, or simply considered to remain fixed. 0=not updated, 1=updated (default)
	update_kinematics	1. Specification whether the water kinematics are updated during iterations or only once per time step. 0=only updated once per time step, 1=full update (default).

Here is an example of this written into the htc-input file.

```
begin HYDRO_ELEMENT ;
  mbody_name cylinder ;
  buoyancy 1 ;
  update_states 1 ; (0: no dynamic interaction, 1: fully coupled solution)
  hydrosections auto 4 ; dist, of hydro calculation points from 1 to nsec
  nsec 2; z      Cm Cd A      Aref  width dr/dz Cd_a_(quad) Cm_a Cd_a_lin Aif
  sec   0.0  1  1  3.404  3.404  2.082  0.0  0.0      0.0  0.0      3.023;
  sec   5.0  1  1  3.404  3.404  2.082  0.0  0.0      0.0  0.0      3.023;
end HYDRO_ELEMENT ;
```

This example shows a flooded cylindrical element (l=5 m, d= 2,082 m and t=60mm).

## Description of the water\_kinematics\_dll format.

```
subroutine init(inputfile,t0,t1,dt) implicit none
character*(*) :: inputfile
real*8          :: t0 ! start time for simulation
real*8          :: t1 ! stop time for simulation
real*8          :: dt ! time increment
!DEC$ ATTRIBUTES DLLEXPORT, ALIAS:'init'::init
end subroutine init

!-----
subroutine set_new_time(time)
implicit none
!DEC$ ATTRIBUTES DLLEXPORT, ALIAS:'set_new_time'::set_new_time
real*8          :: time

end subroutine set_new_time

!-----
subroutine get_sea_elevation(posxy_h,elevation)
implicit none
!DEC$ ATTRIBUTES DLLEXPORT, ALIAS:'get_sea_elevation'::get_sea_elevation
real*8,dimension(2) :: posxy_h ! horizontal position coordinates
real*8              :: elevation ! water height above mean water
! level, positive upwards
end subroutine get_sea_elevation

!-----
!DEC$ ATTRIBUTES DLLEXPORT, ALIAS:'get_kinematics'::get_kinematics
real*8,dimension(3) :: pos_h,&
                    vel_h,&
                    acc_h
real*8              :: pres
end subroutine get_kinematics
```

## User manual to the standard wkin.dll version 2.2.

The wkin.dll which is delivered along with the HAWC2 code needs a separate inputfile. The format for these inputs are the same as the HAWC2 main inputfile with usage of begin..end clauses, semi colon separators, exit command etc. Command words are described below.

All command words written below has to be included in an begin .. end clause called wkin\_input:

```
begin wkin_input;
...
end wkin_input;
exit;
```

### Version info:

- |     |      |   |
|-----|------|---|
| 1-0 | TJUL | Basic edition by TJUL   |
| 1-1 | ANMH | Wave field can be read by file and used directly through fft conversion   |
| 1-2 | TJUL | Directional spreading included  |
| 1-3 | ANMH | Bug corrected regarding read on seed number using iredular waves  |
| 1-4 | TJUL | Pierson-Moscowitz spectrum added as option<br>Stream function wave added<br>Possible pre processing of wave field to speed up simulation time and enable many more coefficients |
| 1-5 | TJUL | Bug in stream function wave. Static pressure was included – now removed   |
| 1-6 | TJUL | Bug in stream fuction wave. lateral position was applied instead of vertical in kinematics look-up!!!   |

1-7	TKIM	New wave format for precalculated (high order) wave fields
1-8	ANMH	Update in deterministic irregular waves+bugfix
1-9	TJUL	New option for white noise wave excitation
2-0	TJUL	Bug fix of version 1-9. Version 1-9 had some debug statements included that could mess up the time.
2-1	ANMH	Ported to intel
	ANMH	Correction for high wave numbers in deterministic irregular waves
	TJUL	Embedded stream function wave, phase velocity used instead of group velocity with respect to pregenerated waves
2-2	TJUL	Bug fix. Tightened criteria for jonswap spectrum min-max. Use of real*8 in all internal memory related variables.

### Main commands in the wkin.dll:

Obl.	Command name	Explanation
*	wavetype	1. Type of wave used. (0=regular airy, 1=irregular airy, 2=deterministic irregular airy, 3=regular stream function, 4=general wavemode format)
*	wdepth	1. Water depth [m]. Positive value.

### Sub command *reg\_airy*:

Command that need to be present if the wavetype equals 0 in the main command.

Obl.	Command name	Explanation
*	stretching	1. Wheeler stretching of waves. (0=off, 1=on)
*	wave	1. Significant wave height $H_s$ [m] 2. Wave period $T$ [s]

### Sub command *ireg\_airy*:

Command that need to be present if the wavetype equals 1 in the main command.

Obl.	Command name	Explanation
*	stretching	1. Wheeler stretching of waves. (0=off, 1=on)
*	spectrum	1. Base spectrum used. (1=jonswap, 2= Pierson Moscowitz)
	jonswap	Jonswap spectrum formulation 1. Significant wave height $H_s$ [m] 2. Wave period $T_p$ [s] 3. $\gamma$ parameter [-]. A typical value is 3.3
	pm	Pierson-Moscowitz spectrum 1. Significant wave height $H_s$ [m] 2. Wave period $T_p$ [s]
	wn	White noise. 1. Target variance level [m <sup>2</sup> 2. $f_0$ , minimum frequency 3. $f_1$ , maximum frequency
*	coef	1. Number of coefficients. Normally 200 are used even though higher values are recommended in general. A speed issue... 2. Seed number. A positive integer value.
	spreading	1. Spreading model. (0=none, 1= $K_{2s}$ model also referred to as $K_n$ model) 2. Spreading parameter. If model=1 the parameter is $s$ , a positive integer. The higher value, the less spreading.

Obl.	Command name	Explanation
	pregen	Pre-generation of a wave field (default is on). Using this option the irregular wave field is calculated during initialization phase and only table look-up is done during the time simulation phase. Very fast and still accurate. 1. Pregen option. (0=traditional approach (slow), 1=pregenerated wave field used (default))
	Embed_strf	Embed stream function wave in time series at the time when the otherwise largest wave occurs. The wave kinematics is blended into the irregular waves before and after. Wave time period equals $T_p$ 1. Wave height H [m]

**Sub command *det\_airy*:**

Command that need to be present if the wavetype equals 2 in the main command. This command is used when water kinematics needs to be calculated based on a measured elevation time series.

Obl.	Command name	Explanation
*	file	1. File name for measured wave elevation.
*	nsamples	1. Number of lines present in wave elevation file
*	nskip	1. Number of lines to skip before reading of wave elevation file
*	columns	1. Colum number for time sensor in file. 2. Colum number for wave elevation in file.
	stretching	1. Wheeler stretching of waves. (0=off, 1=on (default))
*	cutoff_frac	1. Fraction of total energy which is discarded in the low and high frequency ranges. Default 1E-5

**Sub command *strf*:**

Stream function wave input.

Obl.	Command name	Explanation
*	wave	1. Significant wave height $H_s$ [m] 2. Wave period T [s]

**Sub command *wavemods*:**

Command that need to be present if the wavetype equals 3 in the main command. This command is used when water kinematics needs to be calculated based on a measured elevation time series.

Obl.	Command name	Explanation
*	filename_y	Name of datafile where wave kinematic data is present for the horizontal (wave) direction
*	filename_z	Name of datafile where wave kinematic data is present for the vertical direction
*	datafile_nd	1. Number of depth locations
*	datafile_nt	1. Number of time steps in datafile
*	datafile_t0	2. Time for when wave data is extracted in the datafiles
*	ncol_y	3. Number of columns in datafile_y (time+eta+vel+acc)
*	ncol_z	4. Number of columns in datafile_z (time+eta+vel+acc)

Example of an input file with wave kinematics data for the wavemods option.

```
Wave kinematics input to HAWC2 Wkin.d11
General comment line
```

```

Wave load program "WaveKin" ver. 1.0
Echo file : Outfile.dat
Riso Case 1
Linear Wave
slope 1:25
50 water depth
5 No rel. depths N
0.000 0.400 0.700 0.900 1.000
T v[1]..v[N] acc_v[1]..acc_v[N]
0.000 0.000 -0.016 -0.037 -0.070 -0.119 -0.001 -0.000 -0.001 -0.011 -0.051
0.073 -0.000 -0.016 -0.037 -0.071 -0.123 -0.001 0.001 0.000 -0.008 -0.045
0.146 -0.000 -0.016 -0.037 -0.071 -0.126 -0.001 0.001 0.002 -0.004 -0.039
0.219 -0.000 -0.015 -0.037 -0.072 -0.128 -0.001 0.002 0.004 -0.001 -0.032
0.292 -0.000 -0.015 -0.036 -0.071 -0.130 -0.001 0.003 0.005 0.003 -0.025
0.365 -0.000 -0.015 -0.036 -0.071 -0.132 -0.001 0.003 0.007 0.006 -0.018
0.438 -0.000 -0.015 -0.035 -0.071 -0.133 -0.001 0.004 0.009 0.010 -0.010

```

## Wkin.dll example file

```

begin wkin_input ;
  wavetype 1 ;      0=regular, 1=irregular, 2=deterministic
  wdepth 220.0 ;
;
  begin reg_airy ;
    stretching 0;    0=none, 1=wheeler
    wave 9 12.6;     Hs,T
  end;
;
  begin ireg_airy ;
    stretching 0;    0=none, 1=wheeler
    spectrum 1;      (1=jonswap)
    jonswap 9 12.6 3.3 ; (Hs, Tp, gamma)
    coef 200 1 ;     (coefnr, seed)
    spreading 1 2;   (type(0=off 1=on), s parameter (pos. integer min 1)
  end;
;
  begin det_airy ;
    stretching 0;    0=none, 1=wheeler
    file ..\waves\elevation.dat ;
    nsamples 32768 ;
    nskip 1 ;
    columns 1 5 ;    time column, elevation column
  end;
;
  begin wavemods;   Requires 6 header lines
    datafile_y ../wavedata/wavekin_y.dat;
    datafile_z ../wavedata/wavekin_z.dat;
    datafile_nt 900; number of time steps in file
    datafile_t0 50;  start time for data extraction
    datafile_depth 5; Number of depths in file
    ncol_y 11; Number of data columns in file
    ncol_z 11; Number of data columns in file
  end;
end;
;
exit ;

```

## Soil module

### Main command block - soil

In this command block soil spring/damper forces can be attached to a main body. The formulation is performed so it can be used for other external distributed spring/damper systems than soil.

### Sub command block – soil\_element

Command block that can be repeated as many times as needed. In this command block the distributed soil spring/damper system is set up for a given main body.

Obl.	Command name	Explanation
*	body_name	1. Main_body name to which the soil calculation points are linked.
*	datafile	1. Filename incl. relative path to file containing soil spring properties (example ./soil/soildata.dat)
*	soilsections	1. Distribution method: (“uniform” only possibility) 2. Number of section (min. 2).
	damping_k_factor	1. Rayleigh kind of damping. Factor the linear stiffness coefficients are multiplied with to obtain the damping coefficients. When the factor is 1.0 the vibration is critically damped for the rigid mainbody connected to the spring and dampers.
♣	set	1. Set number in datafile that is used.

\*) Input commands that must be present

♣) Command can be repeated as many times as desired.

### Data format of the soil spring datafile

In the file (which is a text file) different distributed springs can be defined. Each set is located after the “#” sign followed by the set number. Within a set the following data needs to be present.

line 1	“spring type”	(can be “axial”, “lateral” or “rotation_z”)
line 2:	“nrow ndefl”	(nrow is number of rows, ndefl is number of deflections (columns))
line 3..3+nrow	“z_global F(1) F(2),..., F(ndefl)”	First colum is the spring location (global z coordinate). The following colums are Force/length at the different deflection stations. First deflection must be zero. The forces are assumed symmetrical around the zero deflection.

An example is given below:

```
This is a nonlinear soil spring demonstration file
#1
lateral                (axial/lateral)
5 4                    nrow ndefl
      0.0    0.1    0.2    1.0  x1 x2 x3 ..... [m]
0.0  0      15    20    500  Z_G F_1 F_2 F_3 .... F_ndefl [kN/m]
10.0 0      15    20    500
20.0 0      15    20    500
30.0 0      15    20    500
40.0 0      15    20    500
#2
axial                  (axial/lateral)
5 4                    nrow ndefl
      0.0    0.1    0.2    1.0  x1 x2 x3 ..... [m]
0.0  0      150   200   5000 Z_G F_1 F_2 F_3 .... F_ndefl [kN/m]
10.0 0      150   200   5000
20.0 0      150   200   5000
30.0 0      150   200   5000
40.0 0      150   200   5000
#3
rotation_z            (axial/lateral/rotation_z)
5 4                    nrow ndefl
      0.0    0.1    0.2    1.0  x1 x2 x3 ..... [rad]
0.0  0      150   200   5000 Z_G M_1 M_2 M_3 .... M_ndefl [kNm/m]
10.0 0      150   200   5000
20.0 0      150   200   5000
30.0 0      150   200   5000
40.0 0      150   200   5000
```

# External forces through DLL

## Main command block – Force

### Sub command - DLL

This command block can be used when a user defined external force is applied to the structure. The main difference between this DLL format and the normal DLL control interface (used with external controllers) is that added stiffness is calculated initially leading to a more robust a fast solution of the coupled system. This force module can with good results be applied for external equivalent soil-springs or hydrodynamic forces for floating constructions or mooring lines.

Obl.	Command name	Explanation and parameters
	dll	1. Filename incl. relative path to the external DLL (example ./dll/force.dll)
	update	1. Name of subroutine in the DLL.
	mbdy	1. Name of main body to which force dll is coupled.
	node	1. Node number of main body to which force dll is couple

Example of a DLL interface written in fortran90

```

!
! Demonstration of force DLL
!
SUBROUTINE DemoForceDLL(time,x,xdot,xdot2,amat,omega,omegadot,F,M)
!DEC$ ATTRIBUTES DLLEXPORT::DemoForceDLL
!DEC$ ATTRIBUTES ALIAS:'demoforcedll' :: DemoForceDLL
! input
DOUBLE PRECISION          :: time      ! time
DOUBLE PRECISION ,DIMENSION(3) :: x      ! global pos. of reference node
DOUBLE PRECISION ,DIMENSION(3) :: xdot   ! global vel. of reference node
DOUBLE PRECISION ,DIMENSION(3) :: xdot2  ! global acc. of reference node
DOUBLE PRECISION ,DIMENSION(3) :: omega  ! angular vel. of ref. node
                                ! (global base)
DOUBLE PRECISION ,DIMENSION(3) :: omegadot ! angular acc. of ref. node
                                ! (global base)
DOUBLE PRECISION ,DIMENSION(3,3) :: amat  ! rotation matrix (body ->
                                !                                     global)
! output
DOUBLE PRECISION ,DIMENSION(3) :: F      ! External force in reference
                                ! node (global base)
DOUBLE PRECISION ,DIMENSION(3) :: M      ! External moment in reference
                                ! node (global base)
! locals
LOGICAL, SAVE                :: bInit = .FALSE. ! Initialization flag
DOUBLE PRECISION             :: mass = 0.d0    ! Point mass
!
! Initialise on first call
IF (.NOT.bInit) THEN
  bInit = .TRUE.
  ! Open file and read mass
  OPEN(10,FILE="DemoForceDLL_mass.dat")
  READ(10,*) mass
  CLOSE(10)
ENDIF
!
! Calc. force
F = mass*((/0.d0,0.d0,9.81d0/) - xdot2)
M = 0.d0
!
END SUBROUTINE DemoForceDLL

```

## Output

This command **output** can either be a main command block or a sub command block within the `hawc_dll` command block. In the tables below two special columns are introduced. One is *only option* and the other *label option*. When the check mark is 'yes' in *only option* it is possible to use only one of the fields if more than one sensor was defined through the command. The sensor that is used is determined by the number following the *only* command word, see example below.

```
constraint bearing1 shaft_rot 2 only 2;
```

If the *only* command (and the following number) was omitted two sensors was defined; one for the angle and one for the velocity. With the *only* command only the velocity sensor is used in the output since the following number is 2.

With the label option it is possible to make a user defined label of the sensor which is written in the sensor list file. The label command is the # symbol. Everything after the # symbol is used as a label. An example of this could be

```
dll inpvec 1 1 # This is a dummy label ;
```

### Commands used with results file writing

When the output command is used for output files (the most normal purpose) some information regarding file name and format needs to be give

Obl	Command	Explanation
*	filename	1. Filename incl. relative path to outputfile without extension (example <code>./res/output</code> )
	data_format	ASCII or compressed binary output can be chosen. Default is the ASCII format if nothing is specified. 1. format ('hawc_ascii'=ASCII format, 'hawc_binary'=compressed binary format, 'flex_int'=compressed binary format)
	buffer	Buffer size in terms of time steps. When the buffer is full the data are written to data file. Only used together with the ASCII format. 1. buffer size
	time	Time start $t_0$ and stop $t_1$ for output is defined. Default is the entire simulation length if nothing is specified. 1. $t_0$ 2. $t_1$

## File format of HAWC\_ASCII files

Results are written to an ascii formatted data file with the name assigned to the filename variable (eg. filename ./res/resfil ). The data file will have the extension .dat as a standard. The description of the sensors in the data file is given in another textfile with same filename as the data file but the extension .sel. An example could be: ./res/resfil.dat and ./res/resfil.sel.

In the .sel-file, line numer 9 specifies the following parameters: Number of scans, Number of sensors, Duration of output file, Data format (ASCII/BINARY). Example:

```
10 96 20.000 ASCII
```

From line number 13 and onwards, the sensors are specified with the following information:

Sensor number, Variable description, unit, Long description. Example:

```
5      beal angle_speed          rad/s      pitch1 angle speed
```

Full example of the .sel file:

---

```
Version ID : HAWC2MB 4.3w
```

Time : 14:23:28  
Date : 22:11.2006

---

```
Result file : ./res2_rev0/case41c_nohydro.dat
```

---

Scans	Channels	Time [sec]	Format
4500	199	90.000	ASCII

Channel	Variable	Description		
1	Time		s	Time
2	beal angle		deg	shaft_rot angle
3	beal angle_speed		rpm	shaft_rot angle speed
4	beal angle		deg	pitch1 angle
5	beal angle_speed		rad/s	pitch1 angle speed
6	beal angle		deg	pitch2 angle
7	beal angle_speed		rad/s	pitch2 angle speed
8	beal angle		deg	pitch3 angle
9	beal angle_speed		rad/s	pitch3 angle speed

---

## File format of HAWC\_BINARY files

In this file format results are written to a binary unformatted data file with the name assigned to the filename variable (eg. filename ./res/resfil ). The data file will have the extension .dat as a standard. The description of the sensors in the data file is given in another textfile with same filename as the data file but the extension .sel. An example could be: ./res/resfil.dat and ./res/resfil.sel.

The data are scaled to standard 2-byte integers, with a range of 32000 using a scalefactor. The scalefactor is determined for each output sensor

$$s = \frac{MAX(abs(max), abs(min))}{32000}$$

where *max* and *min* are the largest and lowest number in the original data for the sensor. These scale factors are written in the end of the accompanying .sel file. When

converting a binary number to the actual number its just a matter of multiplying the binary numbers of a sensor with the corresponding scalefactor.

In the accompanying text file, which has the extension .sel-file, information of the content in the datafile is stored. In line number 9 the following parameters are specified: Number of scans, Number of sensors, Duration of output file, Data format (ASCII/BINARY). Example:

```
10 96 20.000 ASCII
```

From line number 13 and onwards, the sensors are specified with the following information:

Sensor number, Variable description, unit, Long description. Example:

```
5      beal angle_speed          rad/s      pitch1 angle speed
```

From line number 9+nsensors+5 and upwards the scalefactors are written.

Full example of the .sel file:

```

-----
Version ID : HAWC2MB 4.3
                                                    Time : 14:23:28
                                                    Date  : 22:11.2006
-----
Result file : ./res2_rev0/case41c_nohydro.dat
-----
Scans   Channels   Time [sec]   Format
 4500         9       90.000     ASCII

Channel  Variable Description
-----
 1      Time                s              Time
 2      beal angle          deg            shaft_rot angle
 3      beal angle_speed    rpm            shaft_rot angle speed
 4      beal angle          deg            pitch1 angle
 5      beal angle_speed    rad/s         pitch1 angle speed
 6      beal angle          deg            pitch2 angle
 7      beal angle_speed    rad/s         pitch2 angle speed
 8      beal angle          deg            pitch3 angle
 9      beal angle_speed    rad/s         pitch3 angle speed
-----
Scale factors:
 1.56250E-04
 5.61731E-03
 4.41991E-04
 1.00000E+00
 1.00000E+00
 1.00000E+00
 1.00000E+00
 1.00000E+00
 1.00000E+00
 1.00000E+00

```

An important thing to notice is that in the binary data file all sensors are stored sequentially, i.e. all data for sensor 1, all data for sensor 2, etc. This way of storing the data makes later reading of a sensor extra fast since all data for a sensor can be read without reading any data for the other sensor.

A small matlab code for reading the binary HAWC2 format can be seen below.

```
function sig = ReadHawc2Bin(FileName,path);
% Reads binary HAWC2 results file
% -----
% [t,sig] = ReadFlex4(FileName,Ch);
% filename should be without extension
% -----
% BSKA 26/2-2008
% -----
ThisPath = pwd; cd(path(1,:))

% reading scale factors from *.sel file
fid = fopen([FileName,'.sel'], 'r'); fgets(fid); fgets(fid);
fgets(fid); fgets(fid); fgets(fid); fgets(fid); fgets(fid);
fgets(fid);
tline = fscanf(fid,'%d');
N = tline(1); Nch = tline(2); Time = tline(3); fclose(fid);
ScaleFactor = dlmread([FileName,'.sel'],'',[9+Nch+5 0 9+2*Nch+4
0]);

% reading binary data file
fid = fopen([FileName,'.dat'], 'r'); sig =
fread(fid,[N,Nch],'int16')*diag(ScaleFactor); fclose(fid);

cd(ThisPath)
```

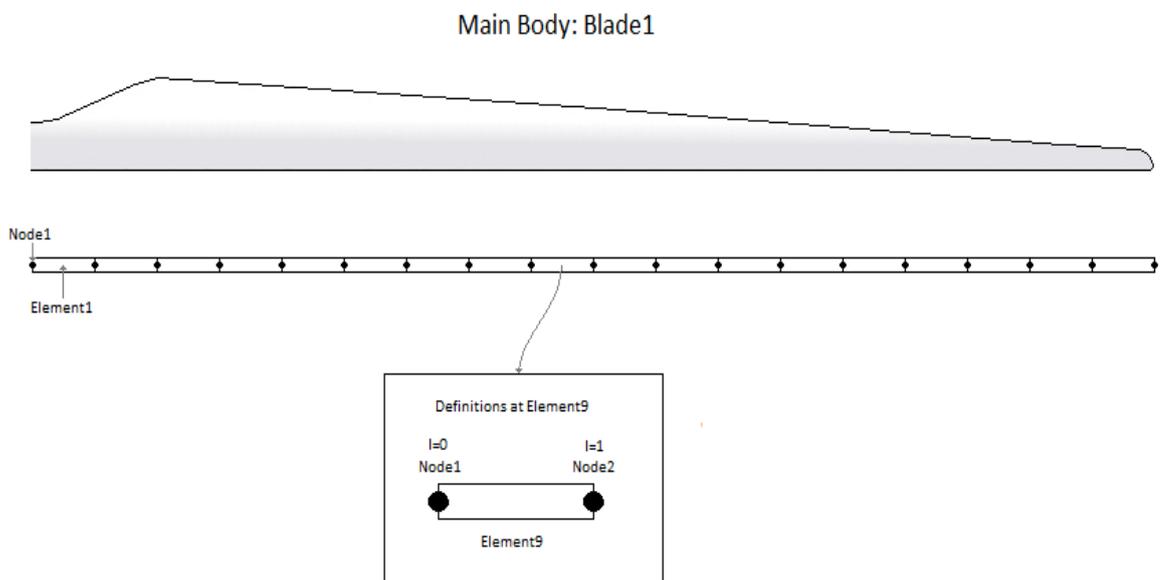
## mbdy (main body output commands)

Command 1	Command 2	Explanation	Only option	Label option
mbdy	forcevec	$F_x, F_y, F_z$ shear force vector defined to output. <ol style="list-style-type: none"> <li>1. Main_body name</li> <li>2. Element number</li> <li>3. Node number on element</li> <li>4. Main_body name of which coordinate system is used for output. “global” and “local” can also be used. Local is around local beam main bending directions.</li> </ol>	yes	yes
mbdy	momentvec	$M_x, M_y, M_z$ moment vector defined to output. <ol style="list-style-type: none"> <li>1. Main_body name</li> <li>2. Element number</li> <li>3. Node number on element</li> <li>4. Main_body name of which coordinate system is used for output. “global” and “local” can also be used. Local is around local beam main bending directions.</li> </ol>	yes	yes

Command 1	Command 2	Explanation	Only option	Label option
mbdy	state	<p>Vector with 3 components of either position, velocity or acceleration of a point on an element defined to output. If 'acg' is used, the acceleration including the gravity contribution is written.</p> <ol style="list-style-type: none"> <li>1. State: 'pos', 'vel', 'acc', 'acg' ("pos"=position, "vel"=velocity, "acc"=acceleration)</li> <li>2. Main_body name</li> <li>3. Element number</li> <li>4. Relative distance from node 1 to node 2 on element</li> <li>5. Main_body name of which coordinate system is used for output. "global" can also be used.</li> </ol>	yes	yes
mbdy	state_at	<p>Vector with 3 components of either position, velocity or acceleration of a point on an element defined to output. The point is offset from the element z axis by an x and y distance in element coordinates.</p> <ol style="list-style-type: none"> <li>1. State: 'pos', 'vel' or 'acc'</li> <li>2. Main_body name</li> <li>3. Element number</li> <li>4. Relative distance from node 1 to node 2 on element</li> <li>5. Main_body name of which coordinate system is used for output. "global" can also be used.</li> <li>6. x-coordinate offset [m]</li> <li>7. y-coordinate offset [m]</li> </ol>	yes	Yes
mbdy	state_at2	<p>Vector with 3 components of either position, velocity or acceleration of a point on an element defined to output. The point is offset from the c2_def centerline z axis by an x and y distance in local c2def centerline coordinates.</p> <ol style="list-style-type: none"> <li>1. State: 'pos', 'vel' or 'acc'</li> <li>2. Main_body name</li> <li>3. Element number</li> <li>4. Relative distance from node 1 to node 2 on element</li> <li>5. Main_body name of which coordinate system is used for output. "global" can also be used.</li> <li>6. x-coordinate offset [m]</li> <li>7. y-coordinate offset [m]</li> </ol>	yes	Yes

Command 1	Command 2	Explanation	Only option	Label option
mbdy	state_rot	<p>Vector with components of either axis and angle (angle [rad], <math>r_1, r_2, r_3</math>), euler parameters (quaternions <math>r_0, r_1, r_2, r_3</math>), euler angles, rotation velocity (<math>\omega</math>-vector) or rotation acceleration (<math>\dot{\omega}</math>-vector) of a point on an element defined to output.</p> <p>For the sensor eulerang_yyx a set of euler angles are created based on the orientation matrix. Be aware that the method used is only valid for rotations in the intervals</p> <p><math>(\theta_x \pm 180^\circ, \theta_y \pm 90^\circ, \theta_z \pm 180^\circ)</math>. The method proj_ang can be used to see how much a blade tip rotates around the pitch axis, but be aware that the angles are how the element is oriented and not necessarily how the local chord is rotated. With the command proj_ang the angles are obtained from the local element orientation 3x3 matrix <math>T_e</math>, seen from the chosen coordinate system using the Atan2 functions (<math>rot_x = \text{atan2}[T_e(2,3), T_e(3,3)]</math>, <math>rot_y = \text{atan2}[T_e(3,1), T_e(1,1)]</math>, <math>rot_z = \text{atan2}[T_e(1,2), T_e(2,2)]</math>).</p> <ol style="list-style-type: none"> <li>1. State : 'axisangle', 'eulerp', 'eulerang_xyz', 'omega', 'omegadot' or proj_ang</li> <li>2. Main_body name</li> <li>3. Element number</li> <li>4. Relative distance from node 1 to node 2 on element</li> <li>5. Main_body name of which coordinate system is used for output. "global" can also be used.</li> </ol>	yes	Yes

This illustration shows how the sensors are placed on an element in terms of local nodes and relative distance.



## Constraint (constraint output commands)

### bearing1

Command 1	Command 2	Explanation	Only option	Label option
constraint	bearing1	Bearing angle and angle velocity defined to output 1. bearing1 name 2. unit of output (1:angle [unit=rad, range $-\pi:\pi$ ], vel [rad/s]; 2:angle [unit=deg, range 0:360], vel [rpm]; 3:angle [unit=deg, range 0:360], vel [rad/s]; 4:angle [unit=deg, range -180:180], vel [rad/s]; 5:angle [unit=deg, range -180:180], vel [deg/s])	Yes	No

### bearing2

Command 1	Command 2	Explanation	Only option	Label option
constraint	bearing2	Bearing angle and angle velocity defined to output 1. bearing1 name 2. unit of output (1:angle [unit=rad, range $-\pi:\pi$ ], vel [rad/s]; 2:angle [unit=deg, range 0:360], vel [rpm]; 3:angle [unit=deg, range 0:360], vel [rad/s]; 4:angle [unit=deg, range -180:180], vel [rad/s]; 5:angle [unit=deg, range -180:180], vel [deg/s])	Yes	No

### bearing3

Command 1	Command 2	Explanation	Only option	Label option
constraint	bearing3	Bearing angle and angle velocity defined to output 1. bearing1 name 2. unit of output (1:angle [unit=rad, range $-\pi:\pi$ ], vel [rad/s]; 2:angle [unit=deg, range 0:360], vel [rpm]; 3:angle [unit=deg, range 0:360], vel [rad/s]; 4:angle [unit=deg, range -180:180], vel [rad/s]; 5:angle [unit=deg, range -180:180], vel [deg/s])	Yes	No

## bearing4

Rotation angle and velocity of the two axis perpendicular to the cardan shaft torsion axis are outputted.

Command 1	Command 2	Explanation	Only option	Label option
constraint	bearing4	Bearing angle and angle velocity defined to output 1. bearing1 name 2. unit of output (1:angle [unit=rad, range $-\pi:\pi$ ], vel [rad/s]; 2:angle [unit=deg, range 0:360], vel [rpm]; 3:angle [unit=deg, range 0:360], vel [rad/s]; 4:angle [unit=deg, range -180:180], vel [rad/s]; 5:angle [unit=deg, range -180:180], vel [deg/s])	Yes	No

### body (old body output commands)

These commands are still part of the code but should be seen as obsolete since they refer to an internal body naming insted of the main\_body names. Please refer to the *mbdy* output commands.

Command 1	Command 2	Explanation	Label option
body	forcevec	$F_x, F_y, F_z$ shear force vector defined to output. Unit [kN] 1. body number 2. Element number 3. Node number on element 4. coordinate system (1=body, 2=global, 3=element)	No
body	momentvec	$M_x, M_y, M_z$ moment vector defined to output. Unit [kNm] 1. body number 2. Element number 3. Node number on element 4. coordinate system (1=body, 2=global, 3=element)	No
body	node_defl	$x, y, z$ deflection vector (within a body) defined to output. Unit [m] 1. body number 2. Element number 3. Node number on element 4. coordinate system (1=body, 2=global, 3=element)	No
body	node_rot	$\theta_x, \theta_y, \theta_z$ , rotations (within a body) define to output. Unit [rad] 1. body number 2. Element number 3. Node number on element 4. coordinate system (1=body, 2=global, 3=element)	No
body	pitchangle	Pitchangle of pitch bearing defined with the old_htc_structure is defined to output. 1. Unit (1=[rad], 2=[deg]) 2. Pitch bearing number	No
body	pitchspeed	Pitch velocity of pitch bearing defined with the old_htc_structure is defined to output. 1. Unit (1=[rad/s], 2=[deg/s]) 2. Pitch bearing number	No
body	node_state	State vector (position, velocity or accelertion) of a given on an element is defined to output. 1. state (“pos”=position, “vel”=velocity, “acc”=acceleration) 2. body name 3. element number 4. $z_{rel}$ (distance between node 1 and 2 divided by element length) 5. coordinate system (1=global)	No

## aero (aerodynamic related commands)

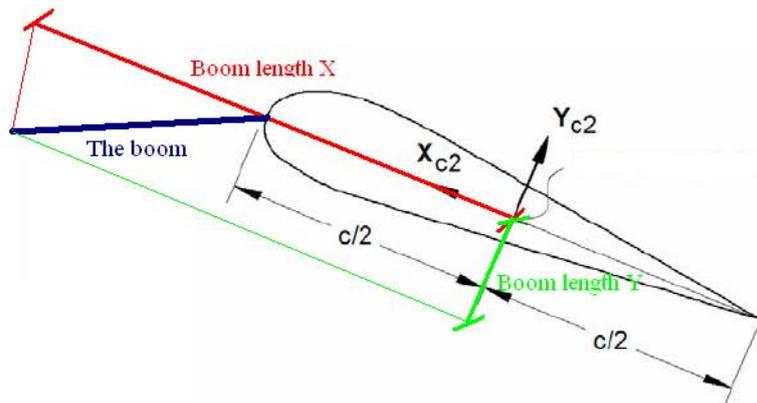
Command 1	Command 2	Explanation	Label option
aero	time	Simulation time to output. No parameters.	No
aero	azimuth	Azimuth angle of selected blade. Zero is vertical downwards. Positive clockwise around blade root y-axis. Unit [deg] 1. Blade number	No
aero	omega	Rotational speed of rotor. Unit [rad/s]	No
aero	vrel	Relative velocity in x-y local aerodynamic plane. Unit [m/s] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	alfa	Angle of attack in x-y local aerodynamic plane. Unit [deg] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	alfadot	Pitch rate term (z-axis rotation) in local aerodynamic plane, as used for non-circulatory contributions. Unit [rad/s] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	sideslip	Side slip angle (from radial flow of BEM expansion) 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	beta	Flap deflection angle (matching the deflection specified by the flap control .dll): 1. Blade number 2. Flap number, according to the order defined in the dynstall_ateflap sub-command block.	No
aero	cl	Instantaneous lift coefficient. Unit [-] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	cd	Instantaneous drag coefficient. Unit [-] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	cm	Instantaneous moment coefficient. Unit [-] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	lift	Lift force at calculation point. Unit [kN/m] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	drag	Drag force at calculation point. Unit [kN/m] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No

Command 1	Command 2	Explanation	Label option
aero	moment	Aerodynamic moment at calculation point. Unit [kNm/m] <ol style="list-style-type: none"> <li>Blade number</li> <li>Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	secforce	Aerodynamic force at calculation point. Local aero coo. Unit [kN/m] <ol style="list-style-type: none"> <li>Blade number</li> <li>Dof number (1=<math>F_x</math>, 2=<math>F_y</math>, 3=<math>F_z</math>)</li> <li>Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	secmoment	Aerodynamic moment at calculation point. Local aero coo. Unit [kN/m] <ol style="list-style-type: none"> <li>Blade number</li> <li>Dof number (1=<math>M_x</math>, 2=<math>M_y</math>, 3=<math>M_z</math>)</li> <li>Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	int_force	Integrated aerodynamic forces from tip to calculational point. NB the integration is performed around the $C_{3/4}$ location. Unit [kN] <ol style="list-style-type: none"> <li>Coordinates system (1=local aero coo, 2=blade ref. system, 3=global, 4=rotor polar)</li> <li>Blade number</li> <li>Dof number (1=<math>M_x</math>, 2=<math>M_y</math>, 3=<math>M_z</math>)</li> <li>Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	int_moment	Integrated aerodynamic moment from tip to calculational point. NB the integration is performed around the $C_{3/4}$ location. Unit [kN] <ol style="list-style-type: none"> <li>Coordinates system (1=local aero coo, 2=blade ref. system, 3=global, 4=rotor polar)</li> <li>Blade number</li> <li>Dof number (1=<math>M_x</math>, 2=<math>M_y</math>, 3=<math>M_z</math>)</li> <li>Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	torque	Integrated aerodynamic forces of all blades to rotor torsion. Unit [kNm]. No parameters	No
aero	thrust	Integrated aerodynamic forces of all blades to rotor thrust. Unit [kN]. No parameters	No
aero	position	Position of calculation point. Unit [m]. Please be aware that if the blade ref system is used, the orientation is in the blade coo, but the origo is still in the hub center. <ol style="list-style-type: none"> <li>Coordinates system (1=local aero coo, 2=blade ref. system, 3=global, 4=rotor polar)</li> <li>Blade number</li> <li>Dof number (1=<math>M_x</math>, 2=<math>M_y</math>, 3=<math>M_z</math>)</li> <li>Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	power	Integrated aerodynamic forces of all blades to rotor torsion multiplied by the rotor speed. Unit [kNm]. No parameters	No

Command 1	Command 2	Explanation	Label option
aero	rotation	Orientation of calculation point. Unit [deg]. <ol style="list-style-type: none"> <li>1. Blade number</li> <li>2. Dof number (1=<math>\theta_x</math>, 2=<math>\theta_y</math>, 3=<math>\theta_z</math>)</li> <li>3. Radius [m] (nearest inner calculation point is used)</li> <li>4. Coordinates system (1=blade_ref. coo, 2=rotor polar coo.)</li> </ol>	No
aero	velocity	Velocity of calculation point. Unit [m/s]. <ol style="list-style-type: none"> <li>1. Coordinates system (1=local aero coo, 2=blade ref. system, 3=global, 4=rotor polar)</li> <li>2. Blade number</li> <li>3. Dof number (1= <math>V_x</math>, 2=<math>V_y</math>, 3=<math>V_z</math>)</li> <li>4. Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	acceleration	Acceleration of calculation point. Unit [m/s <sup>2</sup> ]. <ol style="list-style-type: none"> <li>1. Coordinates system (1=local aero coo, 2=blade ref. system, 3=global, 4=rotor polar)</li> <li>2. Blade number</li> <li>3. Dof number (1= <math>V_x</math>, 2=<math>V_y</math>, 3=<math>V_z</math>)</li> <li>4. Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	tors_e	Aeroelastic torsional twist minus initial static twist of a blade section. <ol style="list-style-type: none"> <li>1. Blade number</li> <li>2. Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	windspeed	Free wind speed seen from the blade. Unit [m/s] <ol style="list-style-type: none"> <li>1. Coordinates system (1=local aero coo, 2=blade ref. system, 3=global, 4=rotor polar)</li> <li>2. Blade number</li> <li>3. Dof number (1= <math>V_x</math>, 2=<math>V_y</math>, 3=<math>V_z</math>)</li> <li>4. Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	spinner_lidar	Sensor emulating a spinner mounted lidar <ol style="list-style-type: none"> <li>1. Measurement type (1=single point, 3=volume average)</li> <li>2. Scan type (1=circular scan, 2=horizontal line (sine sweep), 3=horizontal line (linear sweep), 4=circular 2D scan)</li> <li>3. Focus length [m]</li> <li>4. Measurement angle [deg]</li> <li>5. Scanning velocity [rev/sec]</li> <li>6. Velocity fraction (2D scan)</li> <li>7. Aperture radius (volume) [m]</li> <li>8. Number of points in volume scan</li> <li>9. Wavelength (Volumen) [m]</li> </ol>	No

Command 1	Command 2	Explanation	Label option
aero	induc	Local induced velocity at calculation point. Unit [m/s] 1. Coordinates system (1=local aero coo, 2=blade ref. system, 3=global, 4=rotor polar) 2. Blade number 3. Dof number (1= $V_x$ , 2= $V_y$ , 3= $V_z$ ) 4. Radius [m] (nearest inner calculation point is used)	No
aero	induc_sector_ct	Thrust coefficient at a position on the rotor. Unit [-] 1. Radius [m] 2. Azimuth angle (zero downwards) [deg]	No
aero	induc_sector_cq	Torque coefficient at a position on the rotor. Unit [-] 1. Radius [m] 2. Azimuth angle (zero downwards) [deg]	No
aero	induc_sector_a	Axial induction coefficient at a position on the rotor. Unit [-] 1. Radius [m] 2. Azimuth angle (zero downwards) [deg]	No
aero	induc_sector_am	Tangential induction coefficient at a position on the rotor. Unit [-] 1. Radius [m] 2. Azimuth angle (zero downwards) [deg]	No
aero	induc_a_norm	Axial velocity used in normalization expression of rotor thrust coefficients. The average axial wind velocity incl. induction. Unit [m/s]. No parameters.	No
aero	induc_am_norm	Tangential velocity used in normalization expression of torque coefficient. Average tangential velocity at a given radius. Unit [m/s]. 1. Radius [m]	No
aero	inflow_angle	Angle of attack + rotation angle of profile related to polar coordinates (not pitching). Unit [deg] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	dclalpha	Gradient $dCl/d\alpha$ . Unit [deg <sup>-1</sup> ] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	dcddalpha	Gradient $dCd/d\alpha$ . Unit [deg <sup>-1</sup> ] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	gamma	Circulation strength at calculation point. Unit [m <sup>2</sup> /s] 1. Blade number 2. Radius [m] (nearest inner calculation point is used)	No
aero	lambda	Tip speed ratio, Unit []	No

Command 1	Command 2	Explanation	Label option
aero	windspeed_boom	Free wind speed seen by a boom mounted on a blade section. Coordinate system used “blade ref. system”. Unit [m/s]. <ol style="list-style-type: none"> <li>1. Blade number</li> <li>2. Radius [m] (nearest inner calculation point is used)</li> <li>3. Boom-length X, measured from half chord point positive towards LE [m]</li> <li>4. Boom-length Y, measured from half chord point positive towards pressureside [m]</li> </ol>	No
aero	actuatordiskload	Actuator disk load provide normalized load export for the Actuator Disk Model. <ol style="list-style-type: none"> <li>1. DOF (1=Ft, 2=Fa, 3=Fr)</li> <li>2. Radius [m] (nearest inner calculation point is used)</li> </ol>	No
aero	grid_radius_nd	Aerodynamic calculation point non-dim radius r/R <ol style="list-style-type: none"> <li>1. Number of radial stations outputted (should normally correspond to number of aerodynamic calculation points on a blade)</li> </ol>	No
aero	vawt_induc_x	Induction for a VAWT outputted in tangential polar coordinates <ol style="list-style-type: none"> <li>1. disc number</li> <li>2. azimuth number</li> </ol>	No
aero	vawt_induc_y	Induction for a VAWT outputted in radial polar coordinates <ol style="list-style-type: none"> <li>1. disc number</li> <li>2. azimuth number</li> </ol>	No



*Illustration of the boom coordinates used by the “windspeed\_boom” command.*

### wind (wind output commands)

Command 1	Command 2	Explanation	Only option	Label option
wind	free_wind	Wind vector $V_x$ , $V_y$ , $V_z$ , (wind as if the turbine didn't exist). 1. Coordinate system (1=global, 2=non rotating rotor coordinates (x always horizontal, y always out-of-plane)) 2. x-pos (global coo) 3. y-pos (global coo) 4. z-pos (global coo)	Yes	Yes
wind	free_wind_hor	Horizontal wind component velocity [m/s] and direction [deg] defined to output. Dir=0 when wind equals y-dir. 1. Coordinate system (1=global, 2=non rotating rotor coordinates (x always horizontal, y always out-of-plane)) 2. x-pos (global coo) 3. y-pos (global coo) 4. z-pos (global coo)	Yes	Yes
wind	free_wind_shadow	As sensor "free_wind", but with tower shadow included. 1. Coordinate system (1=global, 2=non rotating rotor coordinates (x always horizontal, y always out-of-plane)) 2. x-pos (global coo) 3. y-pos (global coo) z-pos (global coo)	Yes	Yes

### wind\_wake (wind wake output commands)

Command 1	Command 2	Explanation	Only option	Label option
wind_wake	wake_pos	Position of the wake deficit center after the meandering proces to the downstream end position. x,y and z position is written in meteorological coordinates $(x,y,z)_M=(u,v,w)$ with origo in the position defined with center_pos0 in the general wind commands. 1. wake source number	Yes	Yes

### dll (DLL output commands)

Command 1	Command 2	Explanation	Label option
dll	invec	Value from DLL input vector is defined to output 1. DLL number 2. array index number	yes
dll	outvec	Value from DLL output vector is defined to output 1. DLL number 2. array index number	yes

dll	hawc_dll	<p>Special output commands for the “hawc_dll” format. With this command the dll name can be used in the output definitions</p> <ol style="list-style-type: none"> <li>1. string. Reference name of the dll given in the begin – end hawc_dll input definitions.</li> <li>2. string. “outvec” or “inpvec” can be used. Same definition as previously written above.</li> <li>3. Channel number in the in or out going array.</li> </ol>	yes
dll	type2_dll	<p>Special output commands for the “type2_dll” format. With this command the dll name can be used in the output definitions</p> <ol style="list-style-type: none"> <li>1. string. Reference name of the dll given in the begin – end hawc_dll input definitions.</li> <li>2. string. “outvec” or “inpvec” can be used. Same definition as previously written above.</li> <li>3. Channel number in the in or out going array.</li> </ol>	yes

## hydro (hydrodynamic output commands)

Command 1	Command 2	Explanation	Only option	Label option
hydro	water_surface	Water surface level at a given horizontal location is defined to output (global coordinates). Unit [m] <ol style="list-style-type: none"> <li>1. x-pos</li> <li>2. y-pos</li> </ol>	No	No
hydro	water_vel_acc	Water velocity $V_x$ , $V_y$ , $V_z$ , and acceleration $A_x$ , $A_y$ , $A_z$ vectors defined to output. Unit [m/s] and [m/s <sup>2</sup> ]. <ol style="list-style-type: none"> <li>1. x-pos</li> <li>2. y-pos</li> <li>3. z-pos</li> </ol>	Yes	No
hydro	fm	Inertia force $F_x$ , $F_y$ , $F_z$ contribution from Morisons formula in a given calculation point. Unit [kN] <ol style="list-style-type: none"> <li>1. hydro element number</li> <li>2. sec number</li> <li>3. coordinate system (1=global, 2=local hydro sec coo)</li> </ol>	Yes	No
hydro	fd	Drag force $F_x$ , $F_y$ , $F_z$ contribution from Morisons formula in a given calculation point. Unit [kN] <ol style="list-style-type: none"> <li>1. hydro element number</li> <li>2. sec number</li> <li>3. coordinate system (1=global, 2=local hydro sec coo)</li> </ol>	Yes	No

## general (general output commands)

Command 1	Command 2	Explanation	Label option
general	constant	A constant value is send to output 1. constant value	No
general	step	A step function is created. This function changes from $f_0$ to $f_1$ at time $t_0$ . 1. $t_0$ [sec] 2. $f_0$ 3. $f_1$	No
general	step2	A step function is created. This function changes from $f_0$ to $f_1$ between time $t_0$ and $t_1$ using linear interpolation. 1. $t_0$ [sec] 2. $t_1$ [sec] 3. $f_0$ 4. $f_1$	No
general	step3	A step function is created. This function changes from $f_0$ to $f_1$ between time $t_0$ and $t_1$ using a continous sinus <sup>2</sup> interpolation function. 1. $t_0$ [sec] 2. $t_1$ [sec] 3. $f_0$ 4. $f_1$	No
general	time	The time is send to output. No parameters	No
general	deltat	The time increment is send to output. No parameters	No
general	harmonic	A harmonic function is send to output $F(t) = A \sin(2\pi f_0 t) + k$ 1. A 2. $f_0$ 3. k	No
general	harmonic2	A harmonic function is send to output $F(t) = \begin{cases} 0 & t < t_0 \\ A \sin(2\pi f_0 (t - t_0)) + k & t_0 \leq t \leq t_1 \\ 0 & t > t_1 \end{cases}$ 1. A 2. $f_0$ 3. k 4. $t_0$ 5. $t_1$	No
general	stairs	A series of steps resulting in a staircase signal is created. 1. $t_0$ time for first step change [s] 2. $f_0$ start value of function 3. Step size 4. Step duration [s] 5. Number of steps	No
general	status	A status flag (mainly for controller purpose) is written. A first time step and first iteration the output value is 0. During the rest of the simulation the value is 1 until last time step where the value is -1.	No

Command 1	Command 2	Explanation	Label option
general	random	A random (uniform distribution) is written <ol style="list-style-type: none"> <li>1. lower limit</li> <li>2. upper limit</li> <li>3. seed number</li> </ol>	No
general	impulse	A step function which return to zero after a certain duration <ol style="list-style-type: none"> <li>1. <math>t_0</math> time for impulse start [s]</li> <li>2. Impulse duration [s]</li> <li>3. <math>f_0</math> impulse level</li> </ol>	No

## Output\_at\_time (output at a given time)

This command is especially useful if a snapshot of loads or other properties are required at a specific time. This is mostly used for writing calculated aerodynamic properties as function of blade location. The command block can be repeated as many times as needed (e.g. if outputs at more than one time is needed)

The command must be written with the following syntax

`output_at_time keyword time`

where *keyword* is a command listed in the subsections below. So far only the command `aero` is present. The last command word *time* is the time in seconds from simulation start to which the output are written.

### aero (aerodynamic output commands)

The first line in the `output_at` block must be the information regarding which file the outputs are written (the filename command listed in the table below)

Command 1	Explanation	Label option
filename	Filename incl. relative path to output file (example ./output/output_at.dat). 1. filename	No
alfa	Angle of attack [deg]. 1. Blade number	No
alfadot	Pitch rate term (z-axis rotation) in local aerodynamic plane, as used for non-circulatory contributions. Unit [rad/s]. 1. Blade number	No
vrel	Relative velocity [m/s] 1. Blade number	No
cl	Lift coefficient [-] 1. Blade number	No
cd	Drag coefficient [-] 1. Blade number	No
cm	Moment coefficient [-] 1. Blade number	No
lift	Lift force L [N] 1. Blade number	No
drag	Drag force D [N] 1. Blade number	No
moment	Moment force M [Nm] 1. Blade number	No
secforce	Aerodynamic forces [N] 1. Blade number 2. DOF number (1=x,2=y,3=z) 3. Coordinate system (1=aero, 2=blade, 3=global, 4=rotor polar)	No
secmoment	Aerodynamic moments [Nm] 1. Blade number 2. DOF number (1=x,2=y,3=z) 3. Coordinate system (1=aero, 2=blade, 3=global, 4=rotor polar)	No
int_force	Aerodynamic forces integrated from tip to given radius [N] 1. Blade number 2. DOF number (1=x,2=y,3=z) 3. Coordinate system (1=aero, 2=blade, 3=global, 4=rotor polar)	No

Command 1	Explanation	Label option
int_moment	Aerodynamic moment integrated from tip to given radius [N] 1. Blade number 2. DOF number (1=x,2=y,3=z) 3. Coordinate system (1=aero, 2=blade, 3=global, 4=rotor polar)	No
inipos	Initial position of sections in blade coo [m] 1. Blade number 2. DOF number (1=x,2=y,3=z)	No
position	Actual position of section [m] 1. Blade number 2. DOF number (1=x,2=y,3=z) 3. Coordinate system (1=aero, 2=blade, 3=global, 4=rotor polar)	No
velocity	Actual velocity of section [m/s] 1. Blade number 2. DOF number (1=x,2=y,3=z) 3. Coordinate system (1=aero, 2=blade, 3=global, 4=rotor polar)	No
acceleration	Actual acceleration of section [m/s] 1. Blade number 2. DOF number (1=x,2=y,3=z) 3. Coordinate system (1=aero, 2=blade, 3=global, 4=rotor polar)	No
ct_local	Local thrust coefficient [-]. Calculated based on the expression $C_t = \frac{F_{axial} B}{\frac{1}{2} \rho 2\pi r V_{inf}^2}$ 1. Blade number	No
cq_local	Local tangential force coefficient [-]. Calculated based on the expression $C_q = \frac{F_{tan} B}{\frac{1}{2} \rho 2\pi r V_{inf}^2}$ 1. Blade number	No
chord	Chord length [m] 1. Blade number	No
induc	Induced velocity [m/s] 1. Blade number 2. DOF number (1=x,2=y,3=z) 3. Coordinate system (1=aero, 2=blade, 3=global, 4=rotor polar)	No
windspeed	Free windspeed (without induction but incl. tower shadow effects if used) [m/s] 1. Blade number 2. DOF number (1=x,2=y,3=z) 3. Coordinate system (1=aero, 2=blade, 3=global, 4=rotor polar)	No
inflow_angle	Angle of attack + rotation angle of profile related to polar coordinates (not pitching). Unit [deg] 1. Blade number	No
dclalpha	Gradient $dCl/d\alpha$ . Unit [deg <sup>-1</sup> ] 1. Blade number	No
dcddalpha	Gradient $dCd/d\alpha$ . Unit [deg <sup>-1</sup> ] 1. Blade number	No
tiploss_f	The local Prandtl tiploss factor f is written 1. Blade number	No

# Example of main input file

```

begin Simulation;
  time_stop 100;
  solvetype 1 ; (newmark)
  on_no_convergence continue ;
  logfile ./log/oc3_monopile_phase_1.log ;
  animation ./animation/oc3_monopile_phase_1.dat;
;
begin newmark;
  deltat 0.02;
end newmark;
end simulation;
;
begin new_htc_structure;
  beam_output_file_name ./log/oc3_monopile_phase_1_beam.dat;           Optional - Calculated
  beam_properties_of_the_bodies_are_written_to_file
  body_output_file_name ./log/oc3_monopile_phase_1_body.dat;         Optional - Body initial
  position_and_orientation_are_written_to_file
; body_eigenanalysis_file_name ./eigenfrq/oc3_monopile_phase_1_body_eigen.dat;
; structure_eigenanalysis_file_name ./eigenfrq/oc3_monopile_phase_1_strc_eigen.dat ;
;-----
;
begin main_body;          monopile 30m
  name      monopile ;
  type      timoschenko ;
  nbodies   1 ;
  node_distribution c2_def ;
  damping    4.5E-02 4.5E-02 8.0E-01 1.2E-03 1.2E-03 4.5E-04 ;
  begin timoschenko_input;
    filename ./data/Monopile.txt ;
    set 1 1 ;          set subset 1=flexible,2=stiff
  end timoschenko_input;
  begin c2_def;          Definition of centerline (main_body coordinates)
    nsec 7;
    sec 1 0.0 0.0 0.0 0.0 ; x,y,z,twist Mudline
    sec 2 0.0 0.0 -0.1 0.0 ; x,y,z,twist
    sec 3 0.0 0.0 -10.0 0.0 ; x,y,z,twist 50% between mudline and MSL
    sec 4 0.0 0.0 -15.0 0.0 ; x,y,z,twist
    sec 5 0.0 0.0 -20.0 0.0 ; x,y,z,twist MWL
    sec 6 0.0 0.0 -25.0 0.0 ;
    sec 7 0.0 0.0 -30.0 0.0 ;          Monopile flange
  end c2_def ;
end main_body;
;
begin main_body;          tower 80m
  name      tower ;
  type      timoschenko ;
  nbodies   1 ;
  node_distribution c2_def ;
  damping_posdef 6.456E-4 6.45E-4 1.25E-3 1.4E-3 1.4E-3 1.25E-3 ; Mx My Mz Kx Ky Kz , M's raises
  overall_level, K's raises high frequency level
  begin timoschenko_input;
    filename ./data/NREL_5MW_st.txt ;
    set 1 1 ;
  end timoschenko_input;
  begin c2_def;          Definition of centerline (main_body coordinates)
    nsec 8;
    sec 1 0.0 0.0 0.0 0.0 ; x,y,z,twist
    sec 2 0.0 0.0 -10.0 0.0 ;
    sec 3 0.0 0.0 -20.0 0.0 ;
    sec 4 0.0 0.0 -30.0 0.0 ;
    sec 5 0.0 0.0 -40.0 0.0 ;
    sec 6 0.0 0.0 -50.0 0.0 ;
    sec 7 0.0 0.0 -60.0 0.0 ;
    sec 8 0.0 0.0 -77.6 0.0 ;
  end c2_def ;
end main_body;
;
begin main_body;
  name      towertop ;
  type      timoschenko ;
  nbodies   1 ;
  node_distribution c2_def ;
; damping_posdef 9.025E-06 9.025E-06 8.0E-05 8.3E-06 8.3E-06 8.5E-05 ;
damping 2.50E-04 1.40E-04 2.00E-03 3.00E-05 3.00E-05 2.00E-04 ;
concentrated_mass 2 0.0 1.9 0.21256 2.4E5 1741490.0 1.7E5 1741490.0 ; Nacelle mass and inertia
  begin timoschenko_input;
    filename ./data/NREL_5MW_st.txt ;
    set 2 1 ;
  end timoschenko_input;
  begin c2_def;          Definition of centerline (main_body coordinates)
    nsec 2;
    sec 1 0.0 0.0 0.0 0.0 ; x,y,z,twist
    sec 2 0.0 0.0 -1.96256 0.0 ;
  end c2_def ;
end main_body;
;
begin main_body;
  name      shaft ;
  type      timoschenko ;
  nbodies   1 ;
  node_distribution c2_def ;
; damping_posdef 7.00E-3 7.00E-03 7.00E-02 3.48E-04 3.48E-04 1.156E-03 ;
damping_posdef 7.00E-3 7.00E-03 7.00E-02 6.5E-04 6.5E-04 1.84E-02 ;
concentrated_mass 1 0.0 0.0 0.0 0.0 0.0 5025497.444 ;generator equivalent slow shaft
concentrated_mass 5 0.0 0.0 0.0 56780 0.0 0.0 115926 ; hub mass and inertia;

```

```

        begin timoschenko_input;
        filename ./data/NREL_5MW_st.txt ;
        set 3 1 ;
    end timoschenko_input;
    begin c2_def;                Definition of centerline (main_body coordinates)
        nsec 5;
        sec 1 0.0 0.0 0.0      0.0 ; Tower top x,y,z,twist
        sec 2 0.0 0.0 1.0      0.0 ;
        sec 3 0.0 0.0 2.0      0.0 ;
        sec 4 0.0 0.0 3.1071   0.0 ; Main bearing
        sec 5 0.0 0.0 5.0191   0.0 ; Rotor centre
    end c2_def ;
end main_body;
;
begin main_body;
    name      hub1 ;
    type      timoschenko ;
    nbodies   1 ;
    node_distribution c2_def ;
    damping_posdef 2.00E-05 2.00E-05 2.00E-04 3.00E-06 3.00E-06 2.00E-05;
    begin timoschenko_input;
        filename ./data/NREL_5MW_st.txt ;
        set 4 1 ;
    end timoschenko_input;
    begin c2_def;                Definition of centerline (main_body coordinates)
        nsec 2;
        sec 1 0.0 0.0 0.0      0.0 ; x,y,z,twist
        sec 2 0.0 0.0 1.5      0.0 ;
    end c2_def ;
end main_body;
;
begin main_body;
    name      hub2 ;
    copy_main_body hub1;
end main_body;
;
begin main_body;
    name      hub3 ;
    copy_main_body hub1 ;
end main_body;
;
begin main_body;
    name      blad1 ;
    type      timoschenko ;
    nbodies   9 ;
    node_distribution c2_def;
    damping 3.5e-2 5.5e-4 5.0e-4 3.0e-4 0.5e-3 5.5e-3 ;
    damping_posdef 1.16e-4 5.75e-5 6.1e-6 6.5e-4 5.1e-4 6.4e-4 ;
    begin timoschenko_input ;
        filename ./data/NREL_5MW_st.txt ;
        set 5 1 ;                set subset
    end timoschenko_input;
    begin c2_def;                Definition of centerline (main_body coordinates)
        nsec 19 ;
        sec 1      0.0000 0.0000 0.000 0.000      ; x.y.z. twist
        sec 2      -0.0041 0.0010 1.367 -13.308     ;
        sec 3      -0.1058 0.0250 4.100 -13.308     ;
        sec 4      -0.2502 0.0592 6.833 -13.308     ;
        sec 5      -0.4594 0.1087 10.250 -13.308    ;
        sec 6      -0.5699 0.1157 14.350 -11.480    ;
        sec 7      -0.5485 0.0983 18.450 -10.162    ;
        sec 8      -0.5246 0.0832 22.550 -9.011     ;
        sec 9      -0.4962 0.0679 26.650 -7.795     ;
        sec 10     -0.4654 0.0534 30.750 -6.544     ; 50% blade radius
        sec 11     -0.4358 0.0409 34.850 -5.361     ;
        sec 12     -0.4059 0.0297 38.950 -4.188     ;
        sec 13     -0.3757 0.0205 43.050 -3.125     ;
        sec 14     -0.3452 0.0140 47.150 -2.319     ;
        sec 15     -0.3146 0.0084 51.250 -1.526     ;
        sec 16     -0.2891 0.0044 54.667 -0.863     ;
        sec 17     -0.2607 0.0017 57.400 -0.370     ;
        sec 18     -0.1774 0.0003 60.133 -0.106     ;
        sec 19     -0.1201 0.0000 61.500 -0.000     ;
    end c2_def ;
end main_body;
;
begin main_body;
    name      blade2 ;
    copy_main_body blad1;
end main_body;
;
begin main_body;
    name      blade3 ;
    copy_main_body blad1 ;
end main_body;
;
-----
;
begin orientation;
    begin base;
        body monopile;
        inipos 0.0 0.0 20.0 ;          initial position of node 1
        body_eulerang 0.0 0.0 0.0;
    end base;
;
    begin relative;
        body1 monopile last;          indtil videre antages der internt i programmet at der altid kobles
        body2 tower 1;                mellen sidste knude body1 og første knude body 2
        body2_eulerang 0.0 0.0 0.0;
    end relative;
;
    begin relative;
        body1 tower last;
        body2 towertop 1;
    end relative;
;

```

```

        body2_eulerang 0.0 0.0 0.0;
    end relative;
;
begin relative;
    body1_towertop last;
    body2_shaft 1;
    body2_eulerang 90.0 0.0 0.0;
    body2_eulerang 5.0 0.0 0.0;      5 deg tilt angle
    body2_ini_rotvec_d1 0.0 0.0 -1.0 0.5 ; body initial rotation velocity x.y.z.angle velocity[rad/s]
(body 2 coordinates)
;
    body2_ini_rotvec_d1 0.0 0.0 -1.0 0.9424 ; body initial rotation velocity x.y.z.angle
velocity[rad/s] (body 2 coordinates)
    end relative;
;
begin relative;
    body1_shaft last;
    body2_hub1 1;
    body2_eulerang -90.0 0.0 0.0;
    body2_eulerang 0.0 180.0 0.0;
    body2_eulerang 2.5 0.0 0.0;      2.5deg cone angle
end relative;
;
begin relative;
    body1_shaft last;
    body2_hub2 1;
    body2_eulerang -90.0 0.0 0.0;
    body2_eulerang 0.0 60.0 0.0;
    body2_eulerang 2.5 0.0 0.0;      2.5deg cone angle
end relative;
;
begin relative;
    body1_shaft last;
    body2_hub3 1;
    body2_eulerang -90.0 0.0 0.0;
    body2_eulerang 0.0 -60.0 0.0;
    body2_eulerang 2.5 0.0 0.0;      2.5deg cone angle
end relative;
;
begin relative;
    body1_hub1 last;
    body2_bladel 1;
    body2_eulerang 0.0 0.0 0.0;
end relative;
;
begin relative;
    body1_hub2 last;
    body2_blade2 1;
    body2_eulerang 0.0 0.0 0.0;
end relative;
;
begin relative;
    body1_hub3 last;
    body2_blade3 1;
    body2_eulerang 0.0 0.0 0.0;
end relative;
;
        end orientation;
;-----
begin constraint;
;
begin fix0; fixed to ground in translation and rotation of node 1
    body_monopile;
end fix0;
;
begin fix1; fixed relative to other body in translation and rotation
    body1_monopile last;
    body2_tower 1;
end fix1;
;
begin fix1;
    body1_tower last ;
    body2_towertop 1;
end fix1;
;
begin bearing1;                free bearing
    name shaft_rot;
    body1_towertop last;
    body2_shaft 1;
    bearing_vector 2 0.0 0.0 -1.0;      x=coo (0=global.1=body1.2=body2) vector in body2 coordinates
where the free rotation is present
end bearing1;
;
begin fix1;
    body1_shaft last ;
    body2_hub1 1;
end fix1;
;
begin fix1;
    body1_shaft last ;
    body2_hub2 1;
end fix1;
;
begin fix1;
    body1_shaft last ;
    body2_hub3 1;
end fix1;
;
begin bearing2;
    name pitch1;
    body1_hub1 last;
    body2_bladel 1;
        bearing_vector 2 0.0 0.0 -1.0;
end bearing2;
;

```

```

begin bearing2;
  name pitch2;
  body1 hub2 last;
  body2 blade2 1;
  bearing_vector 2 0.0 0.0 -1.0;
end bearing2;
;
begin bearing3;
  name pitch3;
  body1 hub3 last;
  body2 blade3 1;
  bearing_vector 2 0.0 0.0 -1.0;
end bearing3;
end constraint;
;
end new_htc_structure;
;-----
begin wind ;
density          1.25;
wsp              8 ;
horizontal_input 1;
windfield_rotations 0.0 0.0 0.0 ; yaw, tilt, rotation
center_pos0     0.0 0.0 -90.00; hub_height
shear_format    3 0.12;
turb_format     1 ; 0=none, 1=mann,2=flex
tower_shadow_method 1;
tint            0.06 ;
scale_time_start 200;
wind_ramp_factor 0.0 200 0.5 1.0 ;
;-----
begin tower_shadow_potential;
tower_offset 0.0;
nsec 2;
radius 0.0 2.10;
radius -68.10 1.15;
end tower_shadow_potential;
;-----
; This next part is only to be include in case of wake effects being studied
begin wakes;
nsource 35;
source_pos 2548 -2900 -90 ;
source_pos 2123 -2417 -90 ;
source_pos 1706 -1942 -90 ;
source_pos 1281 -1458 -90 ;
source_pos 857 975 -90 ; WT5
source_pos 432 491 -90 ; WT6
source_pos -425 -484 -90 ; WT8
source_pos -850 -968 -90 ; WT9
source_pos -1267 1458 -90 ;
source_pos -1700 1935 -90 ;
source_pos -2125 2419 -90 ;
source_pos 3556 -2533 -90 ;
source_pos 3131 -2049 -90 ;
source_pos 2706 -1565 -90 ;
source_pos 2281 1081 -90 ; WT16
source_pos 1602 308 -90 ; WT17
source_pos 1176 -176 -90 ; WT18
source_pos 751 -660 -90 ; WT19
source_pos 326 -1144 -90 ; WT20
source_pos -99 -1627 -90 ; WT21
source_pos 3915 -1427 -90 ;
source_pos 3486 -943 -90 ;
source_pos 3062 -455 -90 ;
source_pos 2405 -292 -90 ; WT25
source_pos 1927 -836 -90 ; WT26
source_pos 1502 -1319 -90 ; WT27
source_pos 1077 -1803 -90 ; WT28
source_pos 652 -2287 -90 ; WT29
source_pos 4235 -283 -90 ;
source_pos 3813 205 -90 ;
source_pos 3163 944 -90 ;
source_pos 2679 1495 -90 ;
source_pos 2254 1979 -90 ;
source_pos 1829 2463 -90 ;
source_pos 1404 2947 -90 ;
op_data 1.4252392 2 ; 1.8 -23.1 ; 1.87 0.0 rad/sec, pitch [grader] opstrøms;
ble_parameters 0.10 0.008 0;
begin mann_meanderturb ;
create_turb_parameters 33.6 1 3.7 508 0.0 ; L, alfaeps,gamma,seed, highfrq compensation
filename_v ./free_sector_monopile/wake-meander/wake_meand_turb_wsp8_s508_t1800v.bin ;
filename_w ./free_sector_monopile/wake-meander/wake_meand_turb_wsp8_s508_t1800w.bin ;
box_dim_u 16384 1.7578125 ;
box_dim_v 32 90 ;
box_dim_w 32 90 ;
std_scaling 1.0 0.8 0.5 ;
end mann_meanderturb;
;
begin mann_microturb ;
create_turb_parameters 8.0 1.0 1.0 508 1.0 ; L, alfaeps,gamma,seed, highfrq compensation
filename_u ./free_sector_monopile/wake-micro/wake_turb_wsp8_s508_t1800u.bin ;
filename_v ./free_sector_monopile/wake-micro/wake_turb_wsp8_s508_t1800v.bin ;
filename_w ./free_sector_monopile/wake-micro/wake_turb_wsp8_s508_t1800w.bin ;
box_dim_u 128 1.0 ;
box_dim_v 128 1.0 ;
box_dim_w 128 1.0 ;
std_scaling 1.0 1.0 1.0 ;
end mann_microturb;
end wakes;
;-----
begin mann;
create_turb_parameters 33.6 1 3.7 508 1.0 ; L, alfaeps,gamma,seed, highfrq compensation
filename_u ./free_sector_monopile/turb/turb_wsp8_s508_t1800u.bin ;
filename_v ./free_sector_monopile/turb/turb_wsp8_s508_t1800v.bin ;
filename_w ./free_sector_monopile/turb/turb_wsp8_s508_t1800w.bin ;

```

```

        box_dim_u    16384 1.7578125 ;
        box_dim_v    32 3.75;
        box_dim_w    32 3.75;
        std_scaling  1.0 0.8 0.5 ;
    end mann;
end wind;;
begin aero ;
    nblades 3;
    hub_vec shaft -3 ;          rotor rotation vector (normally shaft component directed from pressure to
                                sustion side)
;
    link 1 mbody_c2_def blade1;
    link 2 mbody_c2_def blade2;
    link 3 mbody_c2_def blade3;
    ae_filename      ./data/NREL_5MW_ae.txt;
    pc_filename      ./data/NREL_5MW_pc.txt;
    induction_method 1 ;      0=none, 1=normal
    aerocalc_method 1 ;      0=ingen aerodynamic, 1=med aerodynamic
    aerosections    30 ;
    ae_sets          1 1 1;
    tiploss_method  1 ;      0=none, 1=prandtl
    dynstall_method 2 ;      0=none, 1=stig øye method,2=mhh method
end aero ;
;
-----
begin hydro;
    begin water_properties;
        rho 1027 ; kg/m^3
        gravity 9.81 ; m/s^2
        mwl 0.0 ;
        mudlevel 20.0 ;
        water_kinematics_dll ./wkin_dll.dll ./htc_hydro/reg_airy_h6_t10.inp ;
    end water_properties;
;
    begin hydro_element;
        body_name monopile ;
        hydrosections uniform 50 ; distribution of hydro calculation points from sec 1 to nsec
        nsec 2;
        sec 0.0 1.0 1.0 28.27 28.27 6.0 ; nr z Cm Cd V Vr width
        sec 30.0 1.0 1.0 28.27 28.27 6.0 ; nr z Cm Cd V Vr width
    end hydro_element;
end hydro;
;
-----
begin dll;
    begin hawc_dll;
        filename ./control/bladed2hawc.dll ;
        dll_subroutine regulation ;
        arraysizes 15 15 ;
        deltat 0.02;
        begin output;
            general time ;
            constraint bearing2 pitch1 1; angle and angle velocity written to dll
            constraint bearing2 pitch2 1; angle and angle velocity written to dll
            constraint bearing2 pitch3 1; angle and angle velocity written to dll
            constraint bearing2 shaft_rot 1; angle and angle velocity written to dll (slow speed shaft)
            wind free wind 1 0.0 0.0 -90.55; local wind at fixed position: coo
            general constant 97.0 ; generator exchange ratio
        end output;
;
        begin actions;
            body moment_int shaft 1 3 tovertop 2 ;
        end actions;
    end hawc_dll;
;
    begin hawc_dll;
        filename ./control/pitchservo_pos.dll ;
        dll_subroutine servo ;
        arraysizes 15 15 ;
        deltat 0.02 ;
        begin output;
            general time ;
            dll inpvec 1 2;
            dll inpvec 1 3;
            dll inpvec 1 4;
            constraint bearing2 pitch1 1; angle and angle velocity written to dll 5,6
            constraint bearing2 pitch2 1; angle and angle velocity written to dll 7,8
            constraint bearing2 pitch3 1; angle and angle velocity written to dll 9,10
        end output;
;
        begin actions;
            body bearing_angle pitch1;
            body bearing_angle pitch2;
            body bearing_angle pitch3;
        end actions;
    end hawc_dll;
;
    begin hawc_dll;
        filename ./control/damper.dll ;
        dll_subroutine damp ;
        arraysizes 15 15 ;
        begin output;
            general time ;
            general constant 5.0;
            general constant 10.0;
            general constant -1.0E1 ;
            mbody state vel tovertop 1 1.0 tower;
        end output;
;
        begin actions;
            mbody force_ext tovertop 2 1 tovertop;
            mbody force_ext tovertop 2 2 tovertop;
        end actions;
    end hawc_dll;
end dll;
;

```

```

-----
;
begin output;
  filename ./res/oc3_monopile_phase_1 ;
; time 390.0 450.0 ;
  buffer 1 ;
  general_time;
  data_format hawc_binary;
;
  constraint bearing1 shaft_rot 2; angle and angle velocity
  constraint bearing2 pitch1 5;   angle and angle velocity
  constraint bearing2 pitch2 5;   angle and angle velocity
  constraint bearing2 pitch3 5;   angle and angle velocity
  aero omega ;
  aero torque;
  aero power;
  aero thrust;
  wind free_wind 1 0.0 0.0 -90.0; local wind at fixed position: coo
  hydro water_surface 0.0 0.0 ;      x,y gl. pos
  mbdy momentvec towertop 1 2 towertop # yaw bearing ;
  mbdy forcevec towertop 1 2 towertop # yaw bearing ;
  mbdy momentvec shaft 4 1 shaft # main bearing ;
  mbdy momentvec blade1 3 1 blade1 # blade 1 root ;
  mbdy momentvec blade1 10 1 local # blade 1 50% local e coo ;
  mbdy momentvec hub1 1 2 hub1 # blade 1 root ;
  mbdy momentvec hub2 1 2 hub2 # blade 2 root ;
  mbdy momentvec hub3 1 2 hub3 # blade 3 root ;
  mbdy state pos towertop 1 1.0 global # tower top flange position ;
  mbdy state pos tower 1 0.0 global # tower MSL position ;
  mbdy state pos blade1 18 1.0 blade1 # blade 1 tip pos ;
  mbdy state pos blade2 18 1.0 blade2 # blade 2 tip pos ;
  mbdy state pos blade3 18 1.0 blade3 # blade 3 tip pos ;
  mbdy state pos blade1 18 1.0 global # blade 1 tip pos ;
  aero windspeed 3 1 1 63.0; wind seen from the blade: coo(1=local ae,2=blade,3=global,4=rotor polar),
  aero windspeed 3 1 2 63.0;
  aero windspeed 3 1 3 63.0;
  aero alfa 1 45.0;
  aero alfa 2 45.0;
  aero alfa 3 45.0;
  mbdy momentvec towertop 1 1 tower # tower top -1: below top mass ;
  mbdy forcevec towertop 1 1 tower # tower top -1: below top mass ;
  mbdy momentvec tower 1 1 tower # tower MSL ;
  mbdy forcevec tower 1 1 tower # tower MSL ;
;
  dll outvec 1 1 # time;
  dll outvec 1 2 # pitch angle 1;
  dll outvec 1 3 # pitch vel 1;
  dll outvec 1 4 # pitch angle 2;
  dll outvec 1 5 # pitch vel 2;
  dll outvec 1 6 # pitch angle 3;
  dll outvec 1 7 # pitch vel 3;
  dll outvec 1 8 # gen. azi slow;
  dll outvec 1 9 # gen. speed slow;
  dll outvec 1 10 # free wind x;
  dll outvec 1 11 # free wind y;
  dll outvec 1 12 # free wind z;
  dll outvec 1 13 # gear ratio;
  dll inpvec 1 1 # Mgen slow;
  dll inpvec 1 2 # pitchref 1;
  dll inpvec 1 3 # pitchref 2;
  dll inpvec 1 4 # pitchref 3;
  dll inpvec 1 7 # F;
  dll inpvec 1 8 # Mechanical power generator [kW];
  dll inpvec 1 10 # Pitch rate [rad/s];
  dll inpvec 2 1 # pitch 1;
  dll inpvec 2 2 # pitch 2;
  dll inpvec 2 3 # pitch 3;
  dll outvec 2 1 # time;
  dll outvec 2 2 # pitchref 1;
  dll outvec 2 3 # pitchref 2;
  dll outvec 2 4 # pitchref 3;
  dll outvec 2 5 # pitch angle 1;
  dll outvec 2 6 # pitch speed 1;
  dll outvec 2 7 # pitch angle 2;
  dll outvec 2 8 # pitch speed 2;
  dll outvec 2 9 # pitch angle 3;
  dll outvec 2 10 # pitch speed 3;
end output;
;
exit;

```

Risø's research is aimed at solving concrete problems in the society.

Research targets are set through continuous dialogue with business, the political system and researchers.

The effects of our research are sustainable energy supply and new technology for the health sector.

