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9999.9 TiDynBrk - Time to initiate deployment of the dynamic generator brake [CURRENTLY IGNORED] (s)
10 TTpBrDp1 - Time to initiate deployment of tip brake 1 (s)
100 TTpBrDp2 - Time to initiate deployment of tip brake 2 (s)
9999.9 TTpBrDp3 - Time to initiate deployment of tip brake 3 (s) [unused for 2 blades]

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501     avrSWAP(118) = 9999.9                               ! Settling time (time to st
502 ! Record 119 is reserved
503 ! user defined variables
504     avrSwap(120) = UserVar_SAVE(1)
505     avrSWAP(121) = TTpBrDp(1)                          ! RWE: EventID
506     avrSWAP(122) = TTpBrDp(2)                          ! RWE: EventTime
507     avrSwap(123) = UserVar_SAVE(4)
508     avrSwap(124) = UserVar_SAVE(5)
509     avrSwap(125) = UserVar_SAVE(6)
510     avrSwap(126) = UserVar_SAVE(7)
511     avrSwap(127) = UserVar_SAVE(8)
512     avrSwap(128) = UserVar_SAVE(9)
513     avrSwap(129) = UserVar_SAVE(10)

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//Das Eingangsfeld für die Reglerfunktion mit Daten füllen
// index in avrSwap in C is Fortran index -1
// be sure to add NINT to every record of data type I. else eg Generator contactor gets 1.001 and 0.001
L50_200_mwController_U.Time = avrSwap[1]; //Time;
L50_200_mwController_U.State_prev = avrSwap[119]; //State_prev;
L50_200_mwController_U.EventID = avrSwap[120]; //EventID;
L50_200_mwController_U.EventTime = avrSwap[121]; //EventTime;
L50_200_mwController_U.HSShftV = avrSwap[19]; //HSShftV;
L50_200_mwController_U.HorWindV = avrSwap[26]; //HorWindV;
L50_200_mwController_U.GenState = floor(avrSwap[34]); //GenState;
L50_200_mwController_U.GenPwr = avrSwap[14]; //GenPwr;
L50_200_mwController_U.YawErr = avrSwap[23]; //NacYawErr;

//Aufruf der Regleroutine
getControllerOutput();

//Daten in das BLADED Übergabefeld zurückschreiben;
avrSwap[119] = L50_200_mwController_Y.State; //State; könnte in FAST BladedDLLInterface implementiert werden
avrSwap[41] = L50_200_mwController_Y.B1PitchCom1_SAVE; //B1PitchCom_SAVE Blade1;
avrSwap[42] = L50_200_mwController_Y.B1PitchCom2_SAVE; //B1PitchCom_SAVE Blade2;
avrSwap[43] = L50_200_mwController_Y.B1PitchCom3_SAVE; //B1PitchCom_SAVE Blade3;
avrSwap[34] = L50_200_mwController_Y.GenState_SAVE; //GenState_SAVE;
avrSwap[46] = L50_200_mwController_Y.GenTrq_SAVE; //GenTrq_Dem;
avrSwap[35] = L50_200_mwController_Y.BrkState_SAVE; //BrkState_SAVE;
avrSwap[106] = L50_200_mwController_Y.HSSBrTrq_SAVE; //BrkTorque_SAVE;
avrSwap[123] = L50_200_mwController_Y.ElecPwr_SAVE; //ElecPwr_SAVE;
avrSwap[47] = L50_200_mwController_Y.YawRate_SAVE; //YawRate_SAVE;

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