

Description of Mass data: Observe, Scope and Control selections			
Variable	Description	Units (default)	Signal name
Mass index i	Mass index number (automatically provided)		
Angle Teta_i	Mechanical angle of mass i in the lumped mass model. This variable can be observed and/or sent to machine scopes.	rad	Teta_i
Angular velocity Omega_i	The actual mechanical speed of mass i of the machine shaft.	rad/sec	Omega_i
Torque Tm_i_j	Request for mechanical torques between the different shaft sections of the turbine-generator set. The shaft torque Tm_i_j is the torque on the shaft section connecting masses i and j=i+1. This variable can be observed and/or sent to machine scopes.	Nm	Tm_i_j
Torque Tmss_i	The steady-state mechanical torque applied on mass i. This variable can be observed.	Nm	Tmss_i
Torque Tm_i	Request for external control of mechanical torque applied on mass i. This variable can be controlled.	Nm	Tm_i

Signal identification rules

If the Observe option is selected, the corresponding mass signal becomes automatically available in the observe signal bundle of the machine. It is identified by the signal name. Example:

Teta_2

is the signal made available for observing the Angle variable on mass number 2.

If the Scope option is selected, the selected variable will become available under machine scopes. It will be identified by the signal name followed by the machine name. Example:

Teta_2_ASMX

is the signal name that becomes available for the machine named ASMX and its Angle variable on mass number 2.