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Performance Analysis of an Assembly System: a Case Study

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Abstract

Petri nets are well suited for modelling production systems and analysis of their performance. In this paper we study a flowshop system driven by a set of local command units and a central controller, modelled with Timed Coloured Petri nets by means of CPN Tools. We show that Petri nets can be applied not only to improve its production rate by comparing various algorithms for the controller policy service, but also to analyse the significance of parameters as conveying and mechanical delays, maximum work-in-process or to understand problems appeared in the real system.

Keywords Petri nets, modelling, simulation, manufacturing systems, case study.

1 Introduction

The behaviour of a production system is not only conditioned by mechanical characteristics of the machines, but also by the equipment which ensures their control [4]. The designers of Livbag company\(^1\), a worldwide leader in automotive safety, are confronted with this problem. The expected production targets are far from being met. Some problems, as apparent stoppages of the production, are even noticed. In [8] Plassart established the need for limiting the controller response time to messages from operative parts. He modelled the system with a FIFO policy service. We will extend this study to other policies. Moreover, we will show that Petri nets are also useful in the analysis of the significance of parameters such as conveying delays, maximum work-in-process or the steady state settling and may allow a better understanding about the origin of the encountered problems.

In this article, we assume the reader is familiar with Petri nets (see [7] for a general survey and [5] for coloured Petri nets). In section 2, we present the production system, the operating cycle of the machines and their modelling. In section 3, we settle bounds for mean inter-arrival delay and makespan to be compared with the simulation results shown in section 4. Due to the lack of space, this study turns only on linear flowshop with a single processor (see section 2.3).

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\(^1\)Société Livbag, groupe Autoliv - Route du Beuzit, 29500 Post de Buis, France

2 Assembly system description, classification and modelling

In this section, we describe the architecture of the system and the operating cycle of the machines, then we propose a classification of the assembly lines according to their topology which allows to formalize a station by its characteristics.

2.1 System architecture

The considered production system is an automated assembly process with several machines called stations linked together by conveyors (figure 1). The stations work in an independent way from each other and execute their operating cycle. A station cannot retain and operate more than one part at a given moment. When a station is available (no assembly in progress) and a part is present at its entry, it starts its operating cycle. Storage capacity on conveyors and in the entry of the station is limited by means of sensors.

![System architecture](figure1)

The control of the assembly line is ensured by a central controller which coordinates the various stations. Thus, it has to be considered as a shared resource of the system. In literature, many manufacturing control architectures are identified [2]. They are often declined in three main types from centralized over hierarchical to hierarchically control. Our control architecture is based on a typical hierarchical structure in which an upper level device coordinates the activities of a group of lower level devices in a master-slave manner [6].

In the present case study, the message exchanges are initiated by the local command units. They are operated according to a request transmission and a response reception. The stimulus is then bottom-up and more than one exchange can be running at the same time and then messages
are stored in a buffer. One of our aim is to evaluate the impact of the message service policy.

2.2 Operating cycle of the stations

The operating process of each station can be split up into five phases:

- identification phase, executed as soon as the part enters the station,
- status request phase. After a possible waiting time in the buffer, the request is processed by the controller and a response is sent back to the station. If the processing is not granted, the part is released, otherwise the process goes on,
- assembly phase, operating sequence completely controlled by a programmable logic controller and immediately executed on receiving the status reply,
- data reporting phase. A message with the necessary measurements for traceability purpose is sent to the controller,
- release phase, performed immediately on receiving the acknowledgement from the controller. This phase is also conditionned by the maximum capacity of storage of the next station or maximum work-in-process (WIP for short), which includes parts either on conveying or pending to be processed. In this paper, parts processed by a station are not considered as WIP.

There is a growing demand from the designers of production lines for increasing the number of messages during a cycle, in order to avoid hazardous manipulations or to save raw materials in case of failure during one of the step of the assembly phase for example. Hence, we extend the operating cycle of a station to $M+1$ mechanical treatments with $M$ messages exchanges in-between. It can be depicted for the processing of one part in figure 2.

![Figure 2: Operating cycle of a station.](image)

The durations of mechanical and message processing are specific to each station. In this paper our approach consists in considering these delays constant. To these delays, we have to add waiting time in the message buffer, which depends on the scheduling policy and therefore vary from a part to another.

2.3 Assembly systems modelling

An assembly system, composed by a set $S = \{S_i\}_{1 \leq i \leq N_S}$ of stations and a set $\mathcal{C} = \{C_j\}_{1 \leq j \leq N_C}$ of conveyors, can be viewed as an acyclic oriented graph, whose nodes symbolize stations and conveyors, conveyors transporting parts from a station to another one. Thus, an assembly system is characterized by a relation $\sigma$ from $S$ in $P(S)$ which links each station with its successors list. The set of successors (resp. predecessors) of a station $S_i$ is denoted $\sigma^+(S_i)$ (resp. $\sigma^-(S_i)$).

![Figure 3: Typology of assembly systems.](image)

We only consider in this study systems with single input and output station. This assumption does not imply any restriction. Indeed, the behaviour of a system with multiple inputs or outputs is not modified by the addition of a head or tail station with processing delays equal to zero.

2.4 Characteristics of a station

For a given assembly system, any station $S_i$ with $M_i$ requests, the controller can be modeled by a 4-tuple, called characteristics of the station,

$$\left(\Theta_{\text{conv}_{i,j}}, \varpi_s, \Theta_{\text{mec}_{s,k}}, \Theta_{\text{req}_{s,l}}\right)$$

where

- $\Theta_{\text{conv}_{i,j}}$ is a matrix with the conveyance delays from the upstream stations of $S_i$ ($S_j \in \sigma^{-}(S_i)$),
- $\varpi_s$ is the maximum work-in-process of $S_i$,
- $\Theta_{\text{mec}_{s,k}}$ is a matrix with the mechanical delays ($1 \leq k \leq M_i$),
- $\Theta_{\text{req}_{s,l}}$ is a matrix with delays of request processing by the controller ($1 \leq l \leq M_i$).

In order to simplify the notation, we will omit some subindices in forthcoming equations, where the context allows. Moreover, we denote the sums of these different delays as follows:

- $\Theta_{\text{conv}} = \sum_{k=1}^{M_i+1} \Theta_{\text{mec}_{s,k}}$,
- $\Theta_{\text{req}} = \sum_{l=1}^{M_i} \Theta_{\text{req}_{s,l}}$,
- $\Theta_{\text{stas}} = \Theta_{\text{conv}} + \Theta_{\text{req}}$ (station delay),
- $\Theta_{\text{ctrl}} = \sum_s \Theta_{\text{req}_{s,l}}$ (controller delay).

2.5 Modelling of a station

A station can be modelled using a timed Petri net shown in figure 4, where the timed transitions are depicted with a blank bar. The places STA, CPU, WIP model the availability of their corresponding resource, i.e. the station, the processor(s) and the conveyor(s).
the obtained bounds show the importance of some parameters we should not have taken into account without their prior study.

3.1 Bounds of the inter-arrival delay

There is an intuitive relation between the ready-state behaviour of a system and the notion of repeatable firing sequences, and consequently with the T-semiflows. In [1], Campos et al. give, for any timed Petri net and for any probability distribution function of firing transition delays, the following lower bound $\Gamma_i$ for the mean cycle time in steady-state associated with a transition $t_i$:

$$\Gamma_i \geq \max_{Y \in \{P_{-semiflow}\}} Y^T.P.R.E.D.F_i$$
subject to $Y^T.M_0 = 1$ \quad (1)

where

- $Y$ is a P-semiflow (i.e. $Y^T.C = 0$, $Y \geq 0$, $Y \neq 0$, with $C$ the global incidence matrix),
- $P.R.E.$ is the Pre-incidence matrix,
- $D$ is the diagonal matrix with the mean value of the delays assigned to the transitions,
- $F_i$ is a T-semiflow (i.e. $C X = 0$, $X \geq 0$, $X \neq 0$) whose component corresponding to $t_i$ is equal to 1,
- $M_0$ is the initial marking.

In this study, $\Gamma_i$ corresponds to our minimal inter-arrival delay, where $t_i$ is the last transition in the net modelling the tail station. We have to note that reachability of this bound is not ensured.

Solving the linear programming problem associated with 1, this bound can be computed. Concerning linear flowshop with a single processor, we deduced the following results.

**Property 1 (Single station)** A single station (with single input and output, figure 3-(a)) with characteristics:

$$\left(\theta_{\text{conv}}, \varpi, (\theta_{\text{mm}}, \theta_{\text{req}})\right)$$

has the following inter-arrival delay lower bound:

$$\tau_d = \max \left\{ \frac{\theta_{\text{conv}}}{\varpi}, \theta_{\text{sta}} \right\}$$ \quad (2)

**Property 2 (Linear flowshop)** A linear flowshop (figure 3-(b)) composed of $N_S$ stations with respective characteristics:

$$\left(\theta_{\text{conv}}, \varpi_s, (\theta_{\text{mmS}}), (\theta_{\text{reqS}})\right)$$

has the following inter-arrival delay lower bound:

$$\tau_d = \max \left\{ \max_{s \in [1:N_S]} \left\{ \frac{\theta_{\text{conv}}}{\varpi_s}, \theta_{\text{staS}} \right\}, \sum_{s=1}^{N_S} \theta_{\text{reqS}} \right\}$$ \quad (3)

3.2 Bounds of makespan

In the case of a linear flowshop, we can deduce from (3) lower bounds of the makespan, to be later compared with the simulation results. Two situations arise according to the value of $\tau_d$:
\[ \tau_d = \frac{\theta_{\text{conv}}}{\tau_d} \] or \[ \theta_{\text{conv}}, \] respectively called conveyor and station bound of the system, where \( s \) is the bottleneck station or conveyor. The best case occurs when this resource never waits for a part. Hence, the minimal makespan for \( N \) parts is

\[ \tau_m = \sum_{s=1}^{N_d} (\theta_{\text{data}} + \theta_{\text{conv}}) + (N - 1) \times \tau_d \]  \hspace{1cm} (4)

\[ \tau_d = \theta_{s\text{conv}}, \] called controller bound of the system. The best case occurs when the controller processes continually the received messages, since the initial one for the first part until the final one for the last part. In this case, the minimal makespan for \( N \) parts is obtained by adding \( N \times b \) to the mechanical delays before and after the first and last messages, which depends on station characteristics.

![Graph showing MakeSpan vs Request Processing Delay](image)

Figure 5: Expected simulation results according to request processing delays compared with makespan bounds.

We have to note that these assumptions are only realistic when the controller bound is far enough from the station or conveyor bound. Therefore, we should get simulation results looking like those depicted in figure 5.

To conclude this section, we obtain theoretical optimum for makespan in order to compare them with the simulation results. Moreover the bounds obtained in (3) correspond to either one conveyor or station delay station, or the controller delay. Therefore, we can distinguish three situations and parameters to analyse:

<table>
<thead>
<tr>
<th>Bottleneck Resource</th>
<th>Parameters</th>
</tr>
</thead>
<tbody>
<tr>
<td>Conveyors</td>
<td>Conveying delays and maximum WIP</td>
</tr>
<tr>
<td>Controller</td>
<td>Controller delay</td>
</tr>
<tr>
<td>Stations</td>
<td>Station delays</td>
</tr>
</tbody>
</table>

4 Flowshop simulation results

The notion of time inherent in the system and the similarity of the station behaviour led us naturally to use timed coloured Petri nets. The tool used to perform simulation is CPN Tools\(^2\), maintained by the CPN Group, University of Aarhus, Denmark. It allows edition, simulation and analysis of such class of Petri nets [3]. First, we present the characteristics of the modelled system and the various service policies we tested and then we show the first simulation results and conclusions we draw from them.

\(^2\)www.daimi.au.dk

4.1 Considered system characteristics

For a first set of tests, data were extracted from readings of existing configurations by Livbag, corresponding to the five phases depicted in section 2.2. The delays (expressed in ms) are constant for all stations, except for the assembly phase:

<table>
<thead>
<tr>
<th>Phase</th>
<th>Delays</th>
</tr>
</thead>
<tbody>
<tr>
<td>Conveying</td>
<td>3000</td>
</tr>
<tr>
<td>Maximum WIP</td>
<td>3</td>
</tr>
<tr>
<td>Pre-assembly</td>
<td>750</td>
</tr>
<tr>
<td>Request processing</td>
<td>see figure 6</td>
</tr>
<tr>
<td>Post-assembly</td>
<td>60</td>
</tr>
</tbody>
</table>

Table 1: Station characteristics.

![Assembly delays expressed in ms](image)

Figure 6: Assembly delays expressed in ms.

Unless explicit mention, below refered simulation results correspond to the production of 1000 parts by lines compound of the \( n^{th} \) first stations with these characteristics \((5 \leq n \leq 30)\). The quantity measured is the absolute or relative deviation from the observed makespan to its corresponding theoretical lower bound.

4.2 Service policies

The message exchanges are initiated by the stations. The requests are stored in a buffer and the stations remain locked until the response. Hence, the service policy may have a significant impact on the makespan. In [8], only FIFO was taken into account. Here we extend our study to following algorithms:

<table>
<thead>
<tr>
<th>Acronym</th>
<th>Priority criteria(^3)</th>
</tr>
</thead>
<tbody>
<tr>
<td>RAN</td>
<td>random</td>
</tr>
<tr>
<td>FIFO</td>
<td>first-in first-out</td>
</tr>
<tr>
<td>LIFO</td>
<td>last-in first-out</td>
</tr>
<tr>
<td>FSF</td>
<td>fastest station delay first</td>
</tr>
<tr>
<td>SSF</td>
<td>slowest station delay first</td>
</tr>
<tr>
<td>Push</td>
<td>closest to the head station</td>
</tr>
<tr>
<td>Pull</td>
<td>closest to the tail station</td>
</tr>
</tbody>
</table>

Table 2: Tested service policies.

\(^3\)In case of equality, the secondary criterion is: closest to the tail station.

The first results brought us to add another criterion: lowest work-in-process in the next station. These algorithms are denoted by LWxx, where xx is one of the above.
acronyms. We modeled these policies by means of lists. The existence of various list functions in CPN Tools allowed us to specify easily the priority between tokens.

4.3 Considered system simulation results

We perform simulations for the configuration expounded in section 4.1 with request processing delays varying from 0 ms to around 2000 ms, with especial attention to values close to the station bound. For 30 stations its value is 160 ms. The figure 7 depicts the results for some service policies with this configuration. With such a graph the quality of the different algorithms can be compared. For example, the assumptions done in section 3.2 are very strong for close station and controller bounds is confirmed.

Figure 7: Relative deviation with theoretical makespan bound (30 stations and request processing varying delays).

The table 3 shows the maximum deviation from the theoretical makespan bound with configurations from 5 to 30 stations (expressed in percentage):

From these simulations, some points emerge:

- the service policy have a great impact on the performance. For example, with a configuration of 12 stations with a message process duration of 420 ms, the makespan got with FSF algorithm is 52% higher than the one got with Pull,
- among the policies which do not take into account the work-in-process of the downstream station, a more detailed analysis shows that SSF and Pull are the most performant when the bottleneck is a station. FIFO or Random are better when the controller is overloaded,
- for configurations above 8 stations, algorithms taking into account the work-in-process amount are clearly more performant unlike for lighter configurations. This is probably due to the relative repartition homogeneity of the stations 2 to 8. Indeed, more recent simulations with stations of equal assembly delay show the poor quality of this class of algorithm with such configuration.

However, neither algorithm is really the most performant (even random is far from being the worst). This leads us to conclude that the most appropriate way to get the best policy is simulation, especially for configurations more complex than those we analyse in this paper.

<table>
<thead>
<tr>
<th>RAN</th>
<th>FIFO</th>
<th>LIPO</th>
<th>FSF</th>
<th>SSF</th>
<th>Push</th>
<th>Pull</th>
</tr>
</thead>
<tbody>
<tr>
<td>5</td>
<td>11.1</td>
<td>12.0</td>
<td>10.9</td>
<td>11.5</td>
<td>16.9</td>
<td>17.1</td>
</tr>
<tr>
<td>6</td>
<td>11.3</td>
<td>14.0</td>
<td>17.3</td>
<td>40.3</td>
<td>16.0</td>
<td>40.6</td>
</tr>
<tr>
<td>8</td>
<td>10.2</td>
<td>10.1</td>
<td>10.8</td>
<td>34.3</td>
<td>16.1</td>
<td>36.5</td>
</tr>
<tr>
<td>10</td>
<td>13.7</td>
<td>9.4</td>
<td>16.6</td>
<td>48.4</td>
<td>12.9</td>
<td>44.0</td>
</tr>
<tr>
<td>12</td>
<td>13.3</td>
<td>11.8</td>
<td>18.4</td>
<td>60.2</td>
<td>12.3</td>
<td>48.0</td>
</tr>
<tr>
<td>15</td>
<td>11.5</td>
<td>11.5</td>
<td>17.5</td>
<td>51.4</td>
<td>8.7</td>
<td>38.0</td>
</tr>
<tr>
<td>18</td>
<td>10.2</td>
<td>11.1</td>
<td>15.3</td>
<td>42.5</td>
<td>13.5</td>
<td>48.2</td>
</tr>
<tr>
<td>20</td>
<td>10.8</td>
<td>11.0</td>
<td>13.8</td>
<td>40.2</td>
<td>9.0</td>
<td>53.0</td>
</tr>
<tr>
<td>22</td>
<td>10.3</td>
<td>11.8</td>
<td>13.1</td>
<td>39.8</td>
<td>7.5</td>
<td>40.9</td>
</tr>
<tr>
<td>25</td>
<td>9.7</td>
<td>11.2</td>
<td>13.9</td>
<td>37.6</td>
<td>7.8</td>
<td>27.3</td>
</tr>
<tr>
<td>28</td>
<td>10.3</td>
<td>10.8</td>
<td>13.0</td>
<td>36.2</td>
<td>6.9</td>
<td>21.8</td>
</tr>
<tr>
<td>30</td>
<td>8.7</td>
<td>10.3</td>
<td>12.0</td>
<td>32.6</td>
<td>6.8</td>
<td>25.5</td>
</tr>
</tbody>
</table>

Table 3: Simulation results.

4.4 Other studies

We also studied other problems, such as significance of conveying delays or steady state settling.

4.4.1 Conveying delays and maximum work-in-process

The inequation $t_{ud} \geq \frac{z_{max}}{z_{max}}$ shows that the conveyors delays cannot be disregarded. Although the maximum work-in-process only has to be increased to prevent a conveyor to be a bottleneck resource, the significance of conveying delays and work-in-process must be analysed.

Figure 8: Absolute deviation with theoretical makespan bound (extract from 0 to 45 sec).

The figure 8 exhibits the results of two sets of simulation on 17 stations, 3 as maximum work-in-process and conveying delay varying from 0 to 60 seconds. The first set when the slowest resource is a station (request processing time = 200 ms) and the second when the bottleneck is the controller (request processing time = 400 ms). The respective thresholds for conveying delay to become the penalising...
resource are 29.07 and 40.80 seconds and are depicted as vertical lines in the figure.

The results on other configurations are quite similar. Hence, we can deduce that, in case the bottleneck resource is a station, an increase in the conveying delay implies a nearly equal increase of the makespan. On the contrary if the controller is the slowest resource, a worsening of the inter-arrival delay is noticed. On the other hand, simulations showed that increasing the maximum work-in-process does not improve the makespan. Thus, we can sum up our conclusions as follows:

<table>
<thead>
<tr>
<th>Bottleneck resource</th>
<th>Conclusion</th>
</tr>
</thead>
<tbody>
<tr>
<td>Controller</td>
<td>Conveying delays have few significance</td>
</tr>
<tr>
<td>Stations</td>
<td>Increase the maximum WIP and act according to the new bottleneck</td>
</tr>
</tbody>
</table>

4.4.2 Steady state settling

We also took an interest in the steady state settling. The detection of some periodicity in the inter-arrival delays appeared difficult. So we tackled the problem by studying work-in-process total amount. Indeed, in addition to the proper interest of this quantity, its stability seems intuitively a sufficient condition for the steady state settling. We got results we can summarize as in figure 9 for 500 parts production with 30 stations and 800 ms as request processing time (controller is the bottleneck resource).

![Figure 9: Work-in-process total amount in relation with processing time in seconds.](image)

With this configuration, the Pull and, to a lower extent, the FIFO policy limit the WIP amount whereas the Push one makes it almost maximum. The steady state is established before at least half an hour (resp. an hour) for FIFO (resp. Push) policy.

The case of LIFO is more amazing. Analysing the maximum inter-arrival delays with this policy, we found values as 11 minutes for request processing delays of 400 ms or 36 minutes for 800 ms. This situation corresponds to the apparent production stoppings mentioned in introduction. However the observed unstability is not translated into a significative productivity loss, scarcely 2 minutes for a 5 hours production.

5 Conclusion and future works

The Petri nets allows an efficient modelling, performance analysis and behaviour comprehension of manufacturing processes. By their solid mathematical basis, theoretical results can be proved. Solving the linear programming problems associated with (1) gives us formal optimum throughput bounds for linear flowshops. Similar but more complicated bounds can be deduced for parallel and parallelized flowshops. The existence of numerous tools (CPN Tools in our case) permits the comparison of simulation results with these optima. Although none of tested service policies did not proved to be the most performant, some trends can be drawn from this study. Behaviour as apparent frozen production have been also explained.

Our future works are based on two distinct angles. On the one hand, we will extend the study to other service policies and more complex systems (figure 3). On the other hand, we will develop a tool which would allow to an user without specific knowledge of Petri nets to perform automatic simulation of his system behaviour.

References


