

GECCO 2020 Competition
on the Optimal Camera Placement Problem (OCP)
and the Unicost Set Covering Problem (USCP)

Mathieu Brévilliers*, Julien Kritter, Julien Lepagnot, and Lhassane
Idoumghar

Université de Haute-Alsace, IRIMAS UR 7499, F-68100 Mulhouse, France

December 17, 2019

*Corresponding Author: mathieu.brevilliers@uha.fr

Contents

1	Introduction	3
2	Description of the addressed problems	4
2.1	Academic instances	4
2.1.1	Problem modelling	4
2.1.2	Problem instances	6
2.1.3	Instance file format	7
2.2	Real world instances	8
2.2.1	Problem modelling	8
2.2.2	Problem instances	8
2.2.3	Instance file format	9
3	Competition rules	11
3.1	Registration	11
3.2	Competition tracks	11
3.3	Experimental setting	12
3.4	Submission instructions	12
3.5	Important Dates	13
4	Evaluation procedure	14
4.1	Full coverage check	14
4.2	Ranking	14
4.3	Results	14
5	Dissemination	15

1 Introduction

The use of camera networks is now common to perform various surveillance tasks. These networks can be implemented together with intelligent systems that analyze video footage, for instance, to detect events of interest, or to identify and track objects or persons. According to [9], whatever the operational needs are, the quality of service depends on the way in which the cameras are deployed in the area to be monitored (in terms of position and orientation angles). Moreover, due to the prohibitive cost of setting or modifying such a camera network, it is required to provide *a priori* a configuration that minimizes the number of cameras in addition to meeting the operational needs. In this context, the optimal camera placement problem (OCP) is of critical importance, and can be generically formulated as follows. Given various constraints, usually related to coverage or image quality, and an objective to optimise (typically, the cost), how can the set of positions and orientations which best (optimally) meets the requirements be determined?

More specifically, in this competition, the objective will be to determine camera locations and orientations which ensure complete coverage of the area while minimizing the cost of the infrastructure. To this aim, a discrete approach is considered here: the surveillance area is reduced to a set of three-dimensional *sample* points to be covered, and camera configurations are sampled into so-called *candidates* each with a given set of position and orientation coordinates. A candidate can have several samples within range, and a sample can be seen by several candidates. Now, the OCP comes down to select the smallest subset of candidates which covers all the samples.

According to [7], the OCP is structurally identical to the unicast set covering problem (USCP), which is one of Karp's well-known *NP*-hard problems [6]. The USCP can be stated as follows: given a set of elements I (rows) to be covered, and a collection of sets J (columns) such that the union of all sets in J is I , find the smallest subset $C \subset J$ such that $\bigcup_{e \in C} e = I$. In other words, identify the smallest subset of J which covers I . As pointed out in [7], many papers dealing with the OCP use this relationship implicitly, but few works done on the USCP have been applied or adapted to the OCP, and vice versa. In very recent years however, approaches from the USCP literature have been successfully applied in the OCP context on both academic [4, 3] and real-world [8] problem instances. These works suggest that bridges can be built between these two bodies of literature to improve the results obtained so far on both USCP and OCP problems.

Firstly, the main goal of this competition is to encourage innovative research works in this direction, by proposing to solve OCP problem instances stated as USCP. Secondly, to this day, no benchmark has been established for the OCP, which makes difficult to provide a fair comparison of all various propositions from the OCP literature [7]: this competition is thus an opportunity to propose a benchmark testbed for the OCP. Thirdly, this competition is a way of attracting the interest of the scientific community in new challenging USCP problem instances, given that, to the best of our knowledge, the last challenge on set covering problems was a competition called FASTER (Ferrovie Airo Set covering TENDER), jointly organized by the Italian railway company (Ferrovie dello Stato SpA) and the Italian Operational Research Society (AIRO) in 1994 [5], and whose problem instances are now part of Beasley's standard OR library [2].

2 Description of the addressed problems

The contest gathers 69 OCP problem instances: 32 of them are academic problems similar to those tackled in [3] (various sizes and discretizations of an empty room modeled by a rectangular cuboid with cameras on the ceiling), and 37 of them are real-world problems similar to those tackled in [8] (various sizes and discretizations of urban areas with cameras on the walls of the buildings).

All the data files are available for download on the competition website¹.

2.1 Academic instances

A first set of 32 artificially generated instances are provided for this competition: given the technical specifications of a camera, given a three-dimensional area to monitor, and given the operational need to meet, the objective is to find a minimum set of locations (i.e. position and angular orientation) of this type of camera that ensures a total coverage of this area according to the requested operational need. The next subsection explains in detail the model used for these academic instances (which is similar to the model defined in [3]).

2.1.1 Problem modelling

The monitored area is defined as a rectangular box whose point coordinates (in meters) range from $(0, 0, 0)$ to $(X_{max}, Y_{max}, Z_{max})$ in a Cartesian coordinate system of the three-dimensional Euclidean space R^3 . This area is discretized and approximated by a regular grid of sample points with a step size U (in meters) between two adjacent samples.

A camera is defined by the following technical specifications: its horizontal resolution H_{res} , its vertical resolution V_{res} , and its horizontal field of view H_{fov} (angle in degrees). It has a pyramid of vision, whose base is a rectangle with length $\frac{H_{res}}{OpNeed}$ and width $\frac{V_{res}}{OpNeed}$ (in meters), where $OpNeed$ is the operational need to be met (in pixels per meter). The height of this right pyramid corresponds to the maximal depth of view D_{max} of the camera (in meters), which depends on the operational need. Figure 1 clearly illustrates the horizontal field of view H_{fov} and the height D_{max} of the pyramid of vision. D_{max} is computed with the following equation:

$$D_{max} = \frac{\frac{1}{2} \times \frac{H_{res}}{OpNeed}}{\tan\left(\frac{H_{fov}}{2} \times \frac{\pi}{180}\right)} \quad (1)$$

A candidate (i.e. a camera location) is characterized by a point in the considered discrete grid together with discrete pan and tilt angles. Candidate coordinates (in meters) can range from $(0, 0, Z_{cam})$ to $(X_{max}, Y_{max}, Z_{cam})$ with step size U (in meters). The angular orientation of a candidate is then given by two angles: α is the pan angle, that is the rotation angle of the candidate along the Z axis, and β is the tilt angle, that is the rotation angle along the Y axis (see Figure 2). Values of α and β are discretized with the help of a parameter A , which fixes the step size to the value $\frac{\pi}{A}$. It means that α can take $N_\alpha = 2A$ different values that range in $[0, 2\pi[$. Regarding β , we only consider $N_\beta = \lfloor A/2 \rfloor + 1$

¹<http://www.mage.fst.uha.fr/brevilliers/gecco-2020-ocp-uscp-competition/>

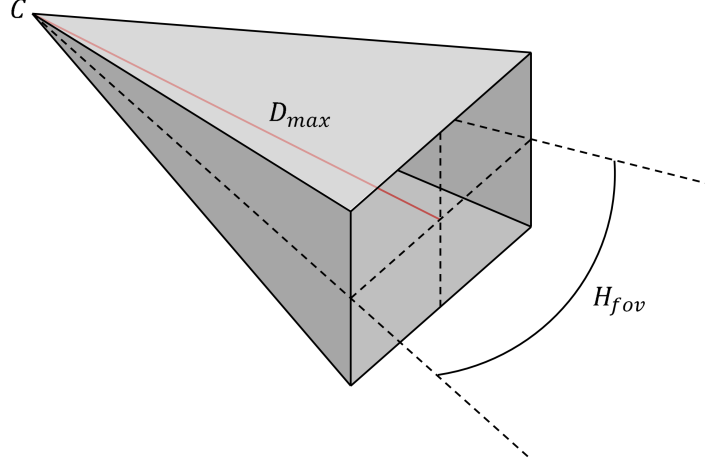


Figure 1: Example of a camera C with horizontal field of view H_{fov} , and whose pyramid of vision has height D_{max} .

different values that range in $[0, \lfloor A/2 \rfloor \times \frac{\pi}{A}]$, given that candidates are above the samples (and thus have to be oriented downward), and given that any candidate with pan angle α and tilt angle $\beta = k \times \frac{\pi}{A}$ such that $\beta < \frac{\pi}{2}$, will be identical to the candidate with same coordinates and pan angle $\alpha' = \alpha + \pi$ and tilt angle $\beta' = \pi - k \times \frac{\pi}{A}$.

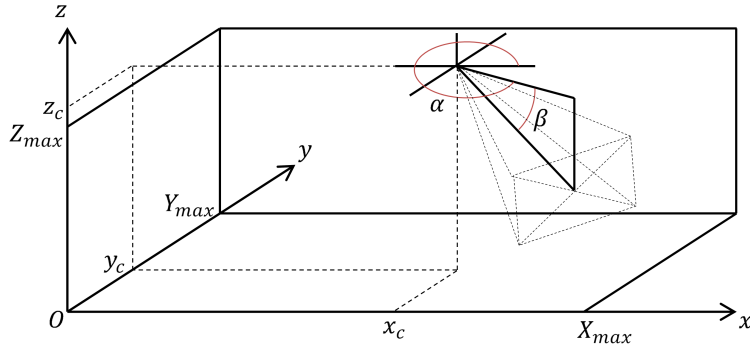


Figure 2: Example of candidate with coordinates (x_c, y_c, z_c) , pan angle α , and tilt angle β .

If the samples are labelled with integers (representing the set of elements to be covered), then any candidate can be modelled as a set of integers (corresponding to the labels of the samples it covers), and the OCP can be formulated as a USCP in a straightforward manner: given the set I of elements (i.e. samples) and a collection J of sets (i.e. candidates), solving the OCP comes down to find the minimum subset of J that covers I .

Now, the following decision variables can be defined:

$$\forall c \in J, x_c = \begin{cases} 1 & \text{if candidate } c \text{ is used,} \\ 0 & \text{otherwise.} \end{cases} \quad (2)$$

Then, the corresponding binary integer linear programming model can be written as follows:

$$\text{Min} \sum_{c \in J} x_c \quad (3)$$

subject to

$$\forall s \in I, \sum_{c \in J: s \in c} x_c \geq 1 \quad (4)$$

$$\forall c \in J, x_c \in \{0, 1\}. \quad (5)$$

The objective function (see Equation 3) minimizes the total number of used candidates. Equation 4 indicates that each sample has to be covered by at least one candidate (full coverage constraint). Equation 5 gives the set of binary constraints needed for the decision variables defined in Equation 2.

2.1.2 Problem instances

Table 1 shows the specifications of the 32 academic instances: instance name, X_{max} , Y_{max} , Z_{max} , Z_{cam} , $OpNeed$, H_{res} , V_{res} , H_{fov} , U , A , number of samples (rows), number of candidates (columns). **It is worth noting that these instances can be significantly reduced before optimization by using classical procedures, i.e. domination and inclusion checks [1].**

Table 1: Specifications of the 32 academic instances.

Name	X_{max}	Y_{max}	Z_{max}	Z_{cam}	$OpNeed$	H_{res}	V_{res}	H_{fov}	U	A	Samples	Candidates
AC_01	5	5	2	2.5	100	1920	1080	65	0.5	4	605	2904
AC_02	10	10	2	2.5	100	1920	1080	65	0.5	4	2205	10584
AC_03	15	15	2	2.5	100	1920	1080	65	0.5	4	4805	23064
AC_04	20	20	2	2.5	100	1920	1080	65	0.5	4	8405	40344
AC_05	25	25	2	2.5	100	1920	1080	65	0.5	4	13005	62424
AC_06	30	30	2	2.5	100	1920	1080	65	0.5	4	18605	89304
AC_07	40	40	2	2.5	100	1920	1080	65	0.5	4	32805	157464
AC_08	50	50	2	2.5	100	1920	1080	65	0.5	4	51005	244824
AC_09	60	60	2	2.5	100	1920	1080	65	0.5	4	73205	351384
AC_10	5	5	2	2.5	500	1920	1080	65	0.5	4	605	2904
AC_11	10	10	2	2.5	500	1920	1080	65	0.5	4	2205	10584
AC_12	15	15	2	2.5	500	1920	1080	65	0.5	4	4805	23064
AC_13	20	20	2	2.5	500	1920	1080	65	0.5	4	8405	40344
AC_14	25	25	2	2.5	500	1920	1080	65	0.5	4	13005	62424
AC_15	30	30	2	2.5	500	1920	1080	65	0.5	4	18605	89304
AC_16	40	40	2	2.5	500	1920	1080	65	0.5	4	32805	157464
AC_17	50	50	2	2.5	500	1920	1080	65	0.5	4	51005	244824
AC_18	60	60	2	2.5	500	1920	1080	65	0.5	4	73205	351384
AC_19	70	70	2	2.5	500	1920	1080	65	0.5	4	99405	477144
AC_20	80	80	2	2.5	500	1920	1080	65	0.5	4	129605	622104
AC_21	90	90	2	2.5	500	1920	1080	65	0.5	4	163805	786264
AC_22	100	100	2	2.5	500	1920	1080	65	0.5	4	202005	969624
AC_23	110	110	2	2.5	500	1920	1080	65	0.5	4	244205	1172184
AC_24	120	120	2	2.5	500	1920	1080	65	0.5	4	290405	1393944
AC_25	130	130	2	2.5	500	1920	1080	65	0.5	4	340605	1634904
AC_26	140	140	2	2.5	500	1920	1080	65	0.5	4	394805	1895064
AC_27	150	150	2	2.5	500	1920	1080	65	0.5	4	453005	2174424
AC_28	160	160	2	2.5	500	1920	1080	65	0.5	4	515205	2472984
AC_29	170	170	2	2.5	500	1920	1080	65	0.5	4	581405	2790744
AC_30	180	180	2	2.5	500	1920	1080	65	0.5	4	651605	3127704
AC_31	190	190	2	2.5	500	1920	1080	65	0.5	4	725805	3483864
AC_32	200	200	2	2.5	500	1920	1080	65	0.5	4	804005	3859224

2.1.3 Instance file format

AC_XX_cover.txt This file contains all the needed information to solve the problem instance AC_XX as a strict USCP (for track 1, see Section 3):

- number of samples and number of candidates,
- then, for each sample s : its integer label s , the number of candidates which cover sample s , and a list of the candidates which cover sample s .

In addition to these cover information, geometric information regarding the problem instances are provided for those who aim at competing in track 2 (see Section 3).

AC_specs.txt This file contains the geometric specifications of each instance, one instance per line, in the following order: instance name, $OpNeed$, H_{res} , V_{res} , H_{fov} , U , and A .

AC_XX_samples.txt This file contains the discrete coordinates (in the regular grid, see Section 2.1.1) of each sample point of problem instance AC_XX, with the following format:

- number of samples,
- then, for each sample s : its integer label, and the integer coordinates (x_s, y_s, z_s) of s in the regular grid which approximate the monitored area.

For convenience, this file stores the coordinates of each sample s in the regular grid, but the real coordinates of s can be easily retrieved with the help of the step size U :

$$(x_s \times U, y_s \times U, z_s \times U). \quad (6)$$

AC_XX_candidates.txt This file contains the discrete coordinates (see Section 2.1.1) of each candidate camera of problem instance AC_XX, with the following format:

- number of candidates,
- then, for each candidate c : its integer label, and the integer coordinates $(x_c, y_c, z_c, \alpha_c, \beta_c)$ of c .

For convenience, this file stores the discrete coordinates of each candidate c , but the real coordinates of c can be easily retrieved with the help of the step size U and the parameter A :

$$(x_c \times U, y_c \times U, z_c \times U, \alpha_c \times \frac{\pi}{A}, \beta_c \times \frac{\pi}{A}). \quad (7)$$

2.2 Real world instances

A second set of 37 real world instances can also be found alongside the academic ones. The main difference lies in the fact that these instances have been generated using map and elevation data from actual urban areas. The objective remains the same: to find the minimum set of camera configurations (position and orientation) which ensures full coverage. The following sections introduce these instances and the method used to generate and model them.

2.2.1 Problem modelling

For these instances, the area to be covered is no longer described by a regular shape. The points to be covered are still represented in a 3D Cartesian coordinate system using the meter as the unit. A point is therefore a simple (x, y, z) triple. The sampling procedure is based on map and elevation data and follows the area’s local infrastructure, meaning no regular position pattern should be expected as far as the points are concerned.

Cameras are modelled using the same method as for the academic instances: their coverage is defined by their resolution, their field of view and an operational need parameter set in pixels-per-meter. The range and frustum computations are roughly identical. The final representation of a configuration is however different, as it is impossible to work on a regular grid when placing cameras on existing city infrastructure. For this reason, in these instances, a camera configuration is defined by two triples: one for position (x_p, y_p, z_p) and one for orientation (x_o, y_o, z_o) . The former follows the same semantics as for points, while the latter is a unit vector oriented to point towards the centre of the frustum pyramid’s base when attached at the camera’s position (see the red line in Figure 1).

While samples are not generated uniformly, participants will most likely notice some patterns in both positions and orientations which can be attributed to the inner-workings of the sampling procedure. The latter uses maps to determine where points should be placed and does so at regular intervals along elements such as roads, alleyways, parking lots, open areas and so on. This procedure requires various parameters, most of which are sampling frequencies which answer questions such as “how often along a road (polyline) should a point be created?” The same applies to the sampling of camera configurations, which follows existing buildings, walls, poles and other such elements. Orientation angles are sampled at regular intervals of $\frac{\pi}{5}$ or $\frac{\pi}{6}$ for panning and $\frac{\pi}{10}$ or $\frac{\pi}{12}$ for tilting. The bounds are similar to those of the academic instances. Points and camera positions were generated every 3 or 5 meters (depending on the instance) along the lines of the city’s geometry. For more detailed information about the sampling procedure, participants are referred to [8].

Aside from the sampling procedure and the resulting model, the real world instance should be solved for the same objective and under the same constraints as the academic ones. The unicost set covering problem model given by Equations (3), (4) and (5) is therefore applicable here and the visibility matrices follow the exact same format in the instance files.

2.2.2 Problem instances

Table 2 gives basic statistics on the 37 real world instances. **The instances have been reduced by applying work reported in [1].** The description is identical to that of

the academic instances, save for the grid parameters which do not apply here.

Table 2: Specifications of the 37 real world instances.

Name	$OpNeed$	H_{res}	V_{res}	H_{fov}	Samples	Candidates
RW_01	25	1920	1080	65	32430	153368
RW_02	25	1920	1080	65	56132	285698
RW_03	25	1920	1080	65	32040	161099
RW_04	25	1920	1080	65	59137	304655
RW_05	25	1920	1080	65	34568	206900
RW_06	25	1920	1080	65	65691	380420
RW_07	25	1920	1080	65	42046	214889
RW_08	25	1920	1080	65	77986	382651
RW_09	25	1920	1080	65	39003	206816
RW_10	25	1920	1080	65	71323	368114
RW_11	25	1920	1080	65	15632	82437
RW_12	25	1920	1080	65	28109	136555
RW_13	25	1920	1080	65	61741	293138
RW_14	25	1920	1080	65	14916	81062
RW_15	25	1920	1080	65	27008	141309
RW_16	25	1920	1080	65	21063	105829
RW_17	25	1920	1080	65	35635	180453
RW_18	25	1920	1080	65	14423	79947
RW_19	25	1920	1080	65	26483	141114
RW_20	25	1920	1080	65	50284	332300
RW_21	25	1920	1080	65	90050	654068
RW_22	25	1920	1080	65	17203	83835
RW_23	25	1920	1080	65	31038	142326
RW_24	25	1920	1080	65	33880	201967
RW_25	25	1920	1080	65	59851	375680
RW_26	25	1920	1080	65	18043	105566
RW_27	25	1920	1080	65	32669	181090
RW_28	25	1920	1080	65	27838	136755
RW_29	25	1920	1080	65	49267	273964
RW_30	25	1920	1080	65	49354	263518
RW_31	25	1920	1080	65	87248	472660
RW_32	25	1920	1080	65	30189	124289
RW_33	25	1920	1080	65	55000	229231
RW_34	25	1920	1080	65	27329	134479
RW_35	25	1920	1080	65	47590	238546
RW_36	25	1920	1080	65	28162	135043
RW_37	25	1920	1080	65	50702	238492

2.2.3 Instance file format

RW_XX_cover.txt This file follows the same format as academic instances (see Section 2.1.3).

RW_specs.txt This file contains the operational parameters of each instance, that is, the first five columns in Table 2.

RW_XX_samples.txt This file contains the real coordinates of each sample point of problem instance RW_XX, with the following format:

- number of samples,
- then, for each sample: its integer label and its real coordinates (x, y, z) in a 3D Cartesian coordinate system (see Section 2.2.1).

RW_XX_candidates.txt This file contains the real coordinates of each candidate camera configuration of problem instance RW_XX, with the following format:

- number of candidates,
- then, for each candidate configuration: its integer label, its position vector (x_p, y_p, z_p) and its orientation unit vector (x_o, y_o, z_o) (see Section 2.2.1).

3 Competition rules

3.1 Registration

Registration is mandatory. Each entrant has to declare his intention to compete as soon as possible by contacting the corresponding author² and providing the following information:

- Name of the team,
- List of the team members,
- Name of the algorithm used to compete,
- Track in which this team will compete with this algorithm (track 1 or 2, see Section 3.2),
- Intention (or no intention) to submit a short description of this algorithm for publication in the GECCO Companion (see Section 5). **To be allowed to submit a contribution, please note that registration has to be done before a strict deadline (see Section 3.5).**

Early registration is strongly encouraged, so that the organizing committee is aware of all entrant teams, and can then keep them informed of any update regarding the organization of the competition (e.g. deadline extension).

Remarks:

- Only 1 algorithm per registration is allowed: for a given registration, the team has to solve all problem instances with the same algorithm.
- The same team can register several times with different algorithms.
- One can be member of several teams.

3.2 Competition tracks

The competition is divided into two tracks.

Track 1: USCP In this first track, the participants are asked to solve the problem instances by only using the visibility matrix provided in AC_XX_cover.txt or RW_XX_cover.txt files (it thus comes down to pure USCP problems). This track is designed for algorithms that are general USCP solvers, i.e. algorithms that don't use any context dependent information (e.g. geometric information of the candidate cameras).

Track 2: OCP In this second track, the participants are allowed to use any available geometric information in addition to the visibility matrix. This track is designed for more OCP specific algorithms that take advantage of context dependent information (e.g. geometric information of the candidate cameras).

²mathieu.brevilliers@uha.fr

3.3 Experimental setting

There is no restriction on the type of algorithm to be used: exact methods, approximation algorithms, hybridizations, new propositions or algorithms from the literature,... **Any algorithm is welcome, but note that the aim of this competition is to promote and highlight new and innovative research works on OCP and/or USCP.**

There is no restriction on the hardware used to solve the problem instances, nor the runtime allowed to solve them.

3.4 Submission instructions

In order to complete their participation and to appear in the competition ranking, the entrants have to follow the submission instructions detailed just below. Please note that all submissions (except GECCO Companion abstracts) have to be sent by email to the corresponding author³.

Solution files The participants will submit to the organizers one solution file for each problem instance. The filename must include the team name, the algorithm name, the track number, and the instance name (in that order). The expected format of a solution file is as follows:

- number of selected candidates,
- a list of the integer labels corresponding to the selected candidates.

An example of solution file is available for download on the competition website⁴.

Remark for participants that will submit an abstract for publication in the GECCO Companion (see Section 5): at the time when they submit their abstract to GECCO, they also have to submit to the organizers the results obtained so far (i.e. the solution files). This first result submission will be used in the review process for the GECCO Companion, but a second result submission will be allowed by the end of the competition (so that all participants will have the same time window to improve their results).

Algorithm description and experimental setting The participants will submit to the organizers an abstract (no more than 2 pages including references) that briefly describes the algorithm used (i.e. the main ideas and/or components of the proposed algorithm), and provides all relevant information regarding the experimental setting used for their submission, e.g.:

- runtime allowed, or runtime needed to reach the submitted solution,
- technical specifications of the computer (CPU, available RAM,...),

³mathieu.brevilliers@uha.fr

⁴<http://www.mage.fst.uha.fr/brevilliers/gecco-2020-ocp-uscp-competition/>

- in case of a non deterministic algorithm, number of runs for each instance,
- in case of a parallel or distributed algorithm, information regarding the hardware, the number of nodes, or any other relevant specification,
- ...

3.5 Important Dates

Table 3 shows all important dates regarding this competition.

Table 3: Important dates

Deadline to register for this competition, to be allowed to submit an abstract for publication in the GECCO Companion	March 20, 2020
Submission deadline for the GECCO Companion abstracts and the corresponding solution files	April 3, 2020
Notification of acceptance for GECCO Companion abstracts	April 17, 2020
Deadline to submit camera-ready abstracts for the GECCO Companion	April 24, 2020
General deadline to register for this competition	May 22, 2020
End of the competition, and submission deadline for: solution files, algorithm description, and experimental setting	June 5, 2020
GECCO 2020 Conference, and announcement of the competition results	July 8-12, 2020

4 Evaluation procedure

4.1 Full coverage check

All the submitted solutions will be checked to ensure the full coverage constraint (and if this constraint is not satisfied, then the solution will be discarded). If a participant does not provide a solution to a problem instance (or provides a solution that does not ensure a full coverage), the organizers will consider that he provides the worst solution (which uses all candidates).

4.2 Ranking

When the competition will be over, the organizers will provide a ranking for each track, and an overall ranking. The method used here is similar to that of the Black Box Optimization Competition (BBComp) ⁵.

For a given track, all participants will be ranked on each problem instance according to the number of candidates needed to cover the samples. A *problem instance score* will then be associated with each rank as follows: if n denotes the number of different solution sizes (and not the number of participants, given that it is likely that some participants gets the same solution size, i.e. the same number of needed cameras), then all the rank k participants will receive $score(k) = \max\{0, \log((n+1)/2) - \log(k)\}$. For each participant, all his problem instance scores are added up to get his *track score*, and the final track ranking will be computed according to these track scores.

The overall ranking will be computed in the same way (regardless of the competition track).

4.3 Results

The results will be announced during GECCO 2020 conference.

No prize will be awarded, except a certificate that will be provided to all entrant teams (stating the team name, the member list, the algorithm name, the competition track, and the achieved rank).

However, all teams are invited to submit a short description of their algorithm for publication in the GECCO Companion (see Section 5). **To be allowed to submit a contribution, please note that registration has to be done before a strict deadline (see Section 3).**

⁵<https://bbcomp.ini.rub.de/faq.html>

5 Dissemination

The organizing committee would like to offer to the participants the opportunity to publish their algorithm descriptions as GECCO Companion abstracts (2-page contributions).

Any submission has to follow GECCO 2020 submission guidelines ⁶ and will be done according to the competition rules (especially regarding registration and submission specific instructions and deadlines, see Section 3).

The organizing committee will review the submissions and then select the top contributing papers (with respect to the obtained results and the innovation of the proposed method).

⁶<https://gecco-2020.sigevo.org/index.html/Papers+Submission+Instructions>

References

- [1] J. E. Beasley. An algorithm for set covering problem. *European Journal of Operational Research*, 31(1):85 – 93, 1987. doi:[https://doi.org/10.1016/0377-2217\(87\)90141-X](https://doi.org/10.1016/0377-2217(87)90141-X).
- [2] J. E. Beasley. Or-library: Distributing test problems by electronic mail. *Journal of the Operational Research Society*, 41(11):1069–1072, 1990. doi:[10.2307/2582903](https://doi.org/10.2307/2582903).
- [3] M. Bréviliers, J. Lepagnot, L. Idoumghar, M. Rebai, and J. Kritter. Hybrid differential evolution algorithms for the optimal camera placement problem. *Journal of Systems and Information Technology*, 20(4):446 – 467, 2018. doi:<https://doi.org/10.1108/JSIT-09-2017-0081>.
- [4] M. Bréviliers, J. Lepagnot, J. Kritter, and L. Idoumghar. Parallel preprocessing for the optimal camera placement problem. *International Journal of Modeling and Optimization*, 8(1):33 – 40, 2018. doi:[10.7763/IJMO.2018.V8.621](https://doi.org/10.7763/IJMO.2018.V8.621).
- [5] A. Caprara, M. Fischetti, and P. Toth. A heuristic method for the set covering problem. *Operations Research*, 47(5):730–743, 1999. doi:<https://doi.org/10.1287/opre.47.5.730>.
- [6] R. M. Karp. *Reducibility among Combinatorial Problems*, pages 85–103. Springer US, Boston, MA, 1972. doi:[10.1007/978-1-4684-2001-2_9](https://doi.org/10.1007/978-1-4684-2001-2_9).
- [7] J. Kritter, M. Bréviliers, J. Lepagnot, and L. Idoumghar. On the optimal placement of cameras for surveillance and the underlying set cover problem. *Applied Soft Computing*, 74:133 – 153, 2019. doi:<https://doi.org/10.1016/j.asoc.2018.10.025>.
- [8] J. Kritter, M. Bréviliers, J. Lepagnot, and L. Idoumghar. On the real-world applicability of state-of-the-art algorithms for the optimal camera placement problem. In *2019 6th International Conference on Control, Decision and Information Technologies (CoDIT)*, pages 1103–1108, April 2019. doi:[10.1109/CoDIT.2019.8820295](https://doi.org/10.1109/CoDIT.2019.8820295).
- [9] J. Liu, S. Sridharan, and C. Fookes. Recent advances in camera planning for large area surveillance: A comprehensive review. *ACM Comput. Surv.*, 49(1):6:1–6:37, May 2016. doi:[10.1145/2906148](https://doi.org/10.1145/2906148).