

S.M.Hadi Sadati, Ph.D.

Postdoc Research Associate in Robotic Systems Engineering
Robotics and Vision in Medicine (RViM) Lab
Dep. Surgical & Interventional Engineering, King's College London, UK.

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Education

King's College London, UK **2014-18**

PhD in Robotics, School of Mathematics and Natural Science, Department of Informatics
Thesis: Decentralized Morphological Stiffness Tunable Interface for Continuum Manipulators
Main supervisors: Dr. Thrishantha Nanayakkara

Sharif University of Technology, Tehran, Iran **2010-12**

M.Sc. in Mechanical Engineering, Applied Design, School of Mechanical Engineering
Thesis: Modeling, Design and Simulation of Falling and Landing Process in a Robotic Cat
Supervisor: Prof. Ali Meghdari

Amirkabir University of Technology (Tehran Polytechnic), Tehran, Iran **2005-10**

B.Sc. in Mechanical Engineering, School of Mechanical Engineering
Thesis: Design and Build of a Passive Walking Biped, Main supervisors: Dr. Mahyar Naraghi

Research Interests

Robotics: Soft Robotics, Medical Robotics, Bio-inspiration, Variable Stiffness, Mechatronics Design, 3D Printing

Medical Robotics: Continuum Medical Robotics, Tooltip Design, Biomechanic System Modeling, Medical Robotic Phantoms, Planning & Automation in Medical Interventions

Morphological Contribution: Functional Morphologies, Morphological Observers, Decentralized Control

Dynamics & Planning: Continuum Dynamics, Dynamical System Approach to Planning & Automation, Bond Graph Multi-Physics Modeling, Domain-Specific Language for Robotics, Passive Dynamics

Research Positions & Visits

Positions

Postdoctoral Research Associate in Robotics System Engineering **May 2019-present**

Robotics and Vision in Medicine (RViM) Lab, Dept. Surgical and Interventional Engineering, School of Biomedical Engineering and Imaging Science, King's College London, London, UK.

Topic: ERC PIONEER- Peri-Ocularly Navigated Exteroceptive Snake Robot for Novel Retinal Interventions

Supervisor: Dr. Christos Bergeles

Postdoctoral Research Associate in Morphological Computation with Spiders' Web **Nov 2017-Apr 2019**

Dep. of Electrical and Electronic Engineering, University of Bristol, Bristol, UK.

Title: Leverhulme Trust Project: Computing with spiders' webs – An inspiration for new sensors and robots

Supervisor: Dr. Helmut Hauser robots

R&D Team Member & Manager **2006-10**
ASAME (Pasargad) Robotic Club, Department of Mechanical Engineering, Amirkabir U.T., Tehran, Iran.
Title: Real Rescue Robot Design Equipped with Serial-link Robotic Manipulators, Supervisor: Dr. M. R. Razfar

Visits

Visiting researcher, Learning Algorithms and Systems Laboratory (LASA), EPFL, Switzerland. **Nov-Dec 2019**
Title: DS-based robust path-planning and control of a Concentric Tube Robot (CTR)
Supervisor: Prof. Aude Billard

Visiting Scholar, Dep. of Electrical and Computer Eng., Clemson University, Clemson, SC, USA. **Nov 2017**
Title: Real-time Path-Planning and Dynamic Control of Long Continuum Manipulators.
Supervisor: Prof. Ian D. Walker

Visiting PhD Student, Dyson School of Design Engineering, Imperial College London, UK. **Jun 2017- Oct 2018**
Title: Bio-inspired Jamming interface for Stiffness Controllable Continuum Manipulators
Supervisor: Dr. Thrishantha Nanayakkara

Industry

R&D Manager, Kaveh Sanaat-e Sharif Company, Tehran, Iran. **2013**
Title: Design and fabrication of a Real Rescue Robot with 5-DOF Manipulator. Supervisor: Mr. A. Torabi Parizi

R&D Engineer, Mangan Industrial Group, Tehran, Iran. **2011- Mar 2012**
Title: Analysis and Optimization of Type “A” Off-shore Crane Boom” and “Lead and Profile Modification of a High-Speed Helical Gears”. Supervisors: Mr. A. Ghasimi, Mr. M. A. Abbaspour

Consultant, Tarbiat Modares University, Tehran, Iran. **2010**
Mechanical Design of a 4-DOF Arm Manipulator. Supervisor: Ms. Z. Mohammadi

Honors & Awards

Grants

King's Global Engagement Partnership Fund, £10.5K, PI **2020-21**
“Dynamical System (DS) Approach for Continuum Medical Robotics Planning & Control”, a joint research by Robotics and Vision in Medicine Lab (RViM), King’s College London, and Learning Algorithms and Systems Laboratory (LASA), École 2Polytechnique Fédérale de Lausanne (EPFL).

UKRI Ideas to Address COVID-19, £1m, Co-I (**Under review**) **2021-22**
“A Data Driven Approach to Reduce Ventilator-Induced Lung Injury (VILI)” by Imperial College London, King’s College London, Oxford University, National Heart & Lung Institute, Guy’s & St Thomas' Hospital

Scholarships & Fellowships

RAEng Research Fellowship Scheme, (**Under university internal review**) **2021-26**
“Reinventing Catheter Steering by Soft Robotics: A Tele-Supervised Semi-Autonomous Wound-Free Robotic Thrombectomy in Acute Stroke (ART)” hosted by King’s College London

Graduate Teaching Scholar (GTS), PhD study at King’s College London, London, UK - £68K + Tuition **2014-17**
Tuition free MSc (Sharif U.T., Iran) & BSc (Amirkabir U.T., Iran) studies **2005-2012**

Travel Grants

Visiting research support, LASA, EPFL, Switzerland – 2K CHF	2019
IEEE Summer School on Control of Surgical Robots (COSUR) travel award, Livorno, Italy - €500	2016
ASME DSCC conference travel grant, Ohio, US - \$200	2015
Conference travel fund, Dept. of Informatics, King's College London, UK - 3 x £500	2015-17

Publication Awards

Excellent Oral Presentation, IEEE ICMAE conference, Prague, Czech Republic.	2017
Best Student Paper Award, IEEE ICIAFS conference, Sri Lanka, Sri Lanka.	2013
Distinguished BSc thesis finalist, Amirkabir U.T., Tehran, Iran.	2010

National Qualification Exams

Rank 14 th among 2K (Top 0.7%), PhD qualification exam in Mechanical Eng. Control & Vibration, Iran	2012
Rank 17 th among 10K (Top 0.2%), MSc qualification exam in Mechanical Engineering, Iran	2010
Rank 697 th among 300K (Top 0.2%), BSc qualification exam in Math, Iran	2005

Selected Publications

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- S.M.H. Sadati**, et al., "TMTDyn: A Matlab Package for Modeling and Control of Hybrid Rigid-Continuum Robots Based on Discretized Lumped System and Reduced Order Models." *IJRR* **2020**
- S.M.H. Sadati**, et al., "Real-time Shape and Tip Force Estimation of a Continuum Appendage from Base Load Readings: A Stiffness Imaging Application", *IEEE RA-L* **2020**
- Z. Mitros, **S.M.H. Sadati**, et al., "Optic Nerve Sheath Fenestration with a Multi-Arm Continuum Robot", *IEEE RA-L* **2020**
- Kayode Sonaike and **S.M.Hadi Sadati**, et al., "Exploiting the Morphology of a Shape Memory Spring as the Active Backbone of a Highly Dexterous Tendril Robot (ATBR)", *IROS* **2020**
- A. Shiva, **S.M.H. Sadati**, et al., "Elasticity vs. Hyperelasticity Considerations in Quasi-Static Model for Real-time Position & Force Estimation of a Soft Manipulator." *SoRo* **2019**
- S. Abad, N. Herzig, **S.M.H. Sadati**, and T. Nanayakkara., "The dynamics of a Bioinspired Hoof on the Slip Reduction." *IEEE T-RO* **2019**
- H. Wegiriya, N. Herzig, S. Abad, **S.M.H. Sadati** and T. Nanayakkara., "Information Gain in a Stiffness Controllable Multimodal Whisker Follicle." *IEEE Sensors* **2019**
- S.M.H. Sadati**, W. Thomas, "Toward Computing with Spider Webs: Computational Setup Realization", *LM Conference* **2018**
- S.M.H. Sadati**, et al., "Three-Dimensional-Printable Thermoactive Helical Interface with Decentralized Morphological Stiffness Control for Continuum Manipulators", *IEEE RA-L* **2018**
- S.M.H. Sadat**, et al., "Control Space Reduction and Real-Time Accurate Modeling of Continuum Manipulators Using Ritz and Ritz-Galerkin Methods", *IEEE RA-L* **2018**
- S.M.H. Sadati**, et al. "A geometry deformation model for braided continuum manipulators." *Frontiers in Robotics and AI* **2017**
- S.M.H. Sadati**, et al., "Continuum Manipulators Mechanics, A Comparative Study of Six Methods with Experiments", *TAROS* **2017**
- S.M.H. Sadati**, et al., "Stiffness Control of Soft Robotic Manipulator for Minimally Invasive Surgery (MIS) Using Scale Jamming". *ICIRA* **2015**

Research Experiences

Continuum Manipulator Modeling

2014-present

Positions: Postdocs at [RViM Lab](#) (King's College London, UK) and Morphological Computation Lab (University of Bristol, UK), PhD at [Morph Lab](#) (King's College London and Imperial College London, UK), Visit at [Prof. Walker's Lab](#) (Clemson University, US)

Main collaborators: Prof. Ian Walker, Dr. Christos Bergeles, Dr. Caleb Rucker

Summary: We presented novel dynamic and static models for continuum manipulators based on reduced-order and discretization approaches suitable for controller and observer design. We have presented unified theoretical framework, comparison of accuracy in experimental studies and numerical performance for different methods showing the superiority of our approaches. We developed [TMTDyn](#) modeling package equipped with a DSL for modelling and control of hybrid rigid-continuum structures.

Robots Planning, Control, and Automation

2019-present

Positions: Postdoc at [RViM Lab](#) (King's College London, UK), Visit at [LASA](#) (EPFL, Switzerland), MSc at [CEDRA](#) (Sharif. U.T., Iran)

Main collaborators: Prof. Aude Billard, Dr. Christos Bergeles, Prof. Ali Meghdari

Summary: We have recently focused on transferring Dynamical System (DS) approach for planning and automation in continuum medical robotics. DS method generates streamline-like paths for task execution that inherently guarantees global convergence, stability, temporal and spatial robustness. I have a 5-year RAEng under review fellowship application on the same topic currently and have done research on active constraint-based medical robot control with [SOFA modeling framework](#) (safe medical robotic navigation via haptic feedback) and shooting-based planning method for non-holonomic dynamical systems (the case of a robotic cat free fall).

Medical Robotics Theory, Design & Fabrication

2014-present

Positions: Postdoc at [RViM Lab](#) (King's College London, UK), PhD at [Morph Lab](#) (King's College London and Imperial College London, UK)

Main collaborators: Dr. Christos Bergeles, Dr. Kaspar Althoefer, Dr. Thrishantha Nanayakkara

Summary: I have been active in development and fabrication of medical robot related theory and technologies since my PhD studies, some of which are: stiffening solutions; tissue palpation; concentric tube robots, ex-vivo real tissue tests; DS and active constraint based planning; robotic phantoms; and more recently patient specific biomedical modelling (EIT image based respiratory system model), and miniature medical sensor and multi-purpose tooltip designs.

Bioinspiration, Morphological Contribution, Smart Material

2010-present

Positions: Postdoc at [RViM Lab](#) (King's College London, UK), Postdoc at [Morphological Computation lab](#) (University of Bristol, UK), PhD at [Morph Lab](#) (King's College London and Imperial College London, UK)

Main collaborators: Dr. Thrishantha Nanayakkara, Dr. Helmut Hauser, Dr. Christos Bergeles

Summary: Bioinspiration has been a main theme in my research, not only as a source of inspiration but for discovering new biological mechanism via robotic design. As a result, I actively pursue morphological contribution, to outsource control tasks to the robot morphology, in my designs via functional structures with smart material, bi-modal multi-purpose mechanisms, and distributed actuation and control methods. Some of my relevant research are spider-web like sensors, active Velcro and tendrils, 3D-printable scale jamming stiffening interfaces, compliant structures for palpation, whisking, and sleep resistance, and recently growing medical cannulas.

System Dynamics

2009-present

Positions: Postdoc at [RViM Lab](#) (King's College London, UK), Visit at [LASA](#) (EPFL, Switzerland), Visit at [Prof. Walker's Lab](#) (Clemson University, US), PhD at [Morph Lab](#) (King's College London and Imperial College London, UK), Postdoc at [RViM Lab](#) (King's College London, UK), MSc at [CEDRA](#) (Sharif. U.T., Iran), BSc and industrial experiences

Main collaborators: Dr. Christos Bergeles, Prof. Ian Walker, Prof. Aude Billard, Dr. Caleb Rucker, Dr. Helmut Hauser, Dr. Thrishantha Nanayakkara, Prof. Ali Meghdari, Dr. Mahyar Naraghi

Summary: I am an expert dynamic system modeler, approaching all my research from a model-based point of view. I have extensive experience with modeling of multi-physics biomedical and continuum systems (e.g. patient specific respiratory system), hybrid continuum-rigid body system models (resulted in development of TMTDyn package), DS-based planning for automation, passive dynamics, and nonholonomic system planning (the case of falling a cat robot).

Mechatronic System Design, Optimization, & Fabrication

2006-present

Positions: Postdoc at [RViM Lab](#) (King's College London, UK), PhD at [Morph Lab](#) (King's College London and Imperial College London, UK), BSc and industrial experiences

Main collaborators: Dr. Christos Bergeles, Dr. Thrishantha Nanayakkara, Dr. Mahyar Naraghi

Summary: I am an expert in robotic and mechatronic system engineering design, optimization, and fabrication. Model-based optimization of the system performance and engineering design of system elements are two key steps in my approach. Some of my robot design are multiple real rescue robots equipped with long series link manipulators, concentric tube and active backbone continuum robots, soft robotics actuator and stiffening mechanisms, robotic vibration and deformable boundary phantom testing platforms, 3D printing functional structures, passive biped walkers and a cat robot.

Computer Science & Programming

2014-present

Positions: Postdoc at [RViM Lab](#) (King's College London, UK), PhD at [Morph Lab](#) (King's College London and Imperial College London, UK)

Main collaborators: Dr. Steffen Zschaler, Dr. Christos Bergeles, Dr. Thrishantha Nanayakkara

Summary: I have extensive experience in different programming languages (with more than 900hr GTS teaching experience) such as Matlab, Maple, C++, Java, Python, Prolog, Assembly, in SOFA, ROS, and Linux environments. We have an ongoing project on developing TMTDyn modeling and control package for hybrid rigid-continuum body structures and a DSL (Distributed System Language) based user interface.

Teaching & Supervision Experiences

Lectures

Lecture, Dept. of Imaging and Biomedical Science, King's College London, UK

2020-21

Subject: "Advanced Mechanics" undergraduate course (50%)

Supervision

"Active Constraints for Surgical Robot using SOFA", M. D. I. Reyzubal, MSc, King's College London, UK 2020

"Shape Memory Tendril Backbone Continuum Manipulator", O. Sonaike, MSc, University of Bristol, UK 2019

"Spiderman Web Shooter", R. Wang, MSc, University of Bristol, UK 2019

"Spider Web Inspired Soft Tactile Sensor Network", S. P. Patni, MSc, University of Bristol, UK 2019

"A Robotic Cat Free-Fall", Z. Chen, MSc, University of Bristol, UK 2018

"Robotic Cat Free Fall: A Design to Imitate Cat-Like Roll" , S. Liang, MSc, University of Bristol, UK	2018
"Electro-Active SMA Velcro Mechanism" , H. Afrisal, MSc, King's College London, UK	2016
"A Variable Stiffness Smart Hydrogel" , D. G. Mosquera, MSc, King's College London, UK	2016
"Low Melting Point Alloy Variable Stiffness Structures" , A. Gupta, MSc, King's College London, UK	2016
"3D-Printable Thermoactive Stiffening Helical Interface" , L. Sullivan, MSc, King's College London, UK	2016
"Elastomer Graphene Electrodes via Laser Scribing" , MSc, King's College London, UK	2016
"Bath Robot with Anisotropic Stiffness Wings" , P. Ghalamchi, BSc (Best Thesis Award), King's College London, UK	2014

Teaching Assistantship

Teaching Assistant , Department of Imaging and Biomedical Science, King's College London, UK	2019
1 subject: "Medical Robotics: Theory and Applications" postgraduate courses (6 hours)	
Graduate Teaching Scholar , Informatics Department, King's College London, UK	2014-17
11 subjects: "Practical Experiences of Programming", "Software Engineering Group Project", "Introduction to Robotics", "Computer Systems I", "Programming Practice", "Real-time Systems", "BSc & MSc Individual Projects", "Adaptive and Robotic Systems", "Elementary Logic and Applications", "Foundation of Computing I" and "Data Structures" postgraduate & undergraduate courses (about 900 hours, 204hr a year)	

Professional Activities & Affiliations

Special Issue Editor , Frontiers in Robotics and AI Journal	2018-19
Title: Research Topic- Current Advances in Soft Robotics: Best Papers from RoboSoft 2018	
Organizing Member of IEEE RAS Soft Robotics Newsletter & Debates	2015-present
Reviewer for 26 scientific journal and 22 conference publications	2015-present
Journals: IJRR, T-RO, SoRo, IEEE RAM, RA-L, Frontiers, JIRS, JRM, JINT, MDPI.	
Conferences: ICRA, IROS, RoboSoft, ICORR, ICRoM, ICIAfS	
Regular & Student Member , IEEE & ASME	2014- present

Professional Trainings & Certificates

Technical

Summer school on Control of Surgical Robots (COSUR) , Livorno, Italy. (1 week)	2016
DOE (Design of Experiments) , TUV INTERCERT International Certification, Iran. (20hr)	2011

Teaching

Enhanced Certificate for Child Workforce Student Ambassador , King's College London, UK	2014
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Software & Programming Skills

MATLAB, Maple, Latex, SolidWorks, Autocad, Ansys Workbench, Comsol, MSC.ADAMS, SOFA, Webots, WorkingModel, ROS, LabView, KissSoft, GearTrax, 20-Sim, MATLAB, C++, Java, Python, Prolog, Assembly

Personal Information

Age: 33, **Gender:** Male, **Nationality:** Iranian

Hobbies: traveling, cycling, reading.

Languages: Persian (Native), English (PhD studies & Postdoc experiences), Arabic (6 years of school courses)

References

Dr. Thrishantha Nanayakkara, Reader in Robotics, Imperial College London, UK. t.nanayakkara@imperial.ac.uk

Prof. Ian D. Walker, Prof. in Robotics, Clemson University, Clemson, SC, USA. iwalker@clemson.edu

Dr. Christos Bergeles, Senior Lecturer in robotics, King's College London, UK. christos.bergeles@kcl.ac.uk

Prof. Kaspar Althoefer, Prof. in Robotics, Queen Mary University of London, UK. k.althoefer@qmul.ac.uk

Publications List

Journal & Editorial Articles

- [1] **S.M.H. Sadati**, S. E. Naghibi, A. Shiva, S. Zschaler, C. Rucker, M. Brendan, L. Renson, K. Althoefer, T. Nanayakkara, H. Hauser and I. Walker., "TMTDyn: A Matlab Package for Modeling and Control of Hybrid Rigid-Continuum Robots Based on Discretized Lumped System and Reduced Order Models." *International Journal of Robotics Research (IJRR)*, **2020**
- [2] **S.M.H. Sadati**, A. Shiva, S. E. Naghibi, C. Rucker, C. Bergeles, I. Walker, H. Hauser, K. Althoefer and T. Nanayakkara., "Real-time Shape and Tip Force Estimation of a Continuum Appendage from Base Load Readings: A Stiffness Imaging Application", *IEEE Robotics & Automation Letters (RA-L)* and *IEEE International Conference on Robotics and Automation (ICRA)*, **2020**
- [3] **S.M.Hadi Sadati**, Perla Maiolino, Fumiya Iida, Thrishantha Nanayakkara and Helmut Hauser, "Editorial: Current Advances in Soft Robotics - Best Papers from RoboSoft 2018", *Frontiers in Robotics and AI*, **2020**
- [4] Z. Mitros, **S.M.H. Sadati**, C. Seneci, E. Bloch, K. Leibbrandt, M. Khadem, L da Cruz, C. Bergeles, "Optic Nerve Sheath Fenestration with a Multi-Arm Continuum Robot", *IEEE Robotics and Automation Letters (RA-L)* and *IEEE International Conference on Intelligent Robots and Systems (IROS)*, **2020**
- [5] Ali Shiva, **S.M.Hadi Sadati**, Yohan Noh, Jane Fras, Ahmad Ataka, Helge Wurdemann, Helmut Hauser, Ian D. Walker, Thrishantha Nanayakkara, Kaspar Althoefer., "Elasticity vs. Hyperelasticity Considerations in Quasi-Static Model for Real-time Position & Force Estimation of a Soft Manipulator." *Soft Robotics*, **2019**
- [6] Sara-Adela Abad, Nicolas Herzig, **S.M.Hadi Sadati**, and Thrishantha Nanayakkara., "The dynamics of a Bioinspired Hoof on the Slip Reduction." *Transaction on Robotics*, **2019**
- [7] Hasitha Wegiriya, Nicolas Herzig, Sara-Adela Abad, **S.M.Hadi Sadati** and Thishantha Nanayakkara., "Information Gain in a Stiffness Controllable Multimodal Whisker Follicle." *IEEE Sensors Journal*, **2019**
- [8] **S.M.H. Sadati**, S. E. Naghibi, A. Shiva, Y. Noh, A. Gupta, I. D. Walker, K. Althoefer, T. Nanayakkara, "Three-Dimensional-Printable Thermoactive Helical Interface with Decentralized Morphological Stiffness Control for Continuum Manipulators", *IEEE Robotics & Automation Letters (RA-L)* and *IEEE International Conference on Robotics and Automation (ICRA)*, **2018**
- [9] **S.M.H. Sadat**, S. E. Naghibi, I. D. Walker, K. Althoefer, T. Nanayakkara, "Control Space Reduction and Real-Time Accurate Modeling of Continuum Manipulators Using Ritz and Ritz-Galerkin Methods", *IEEE Robotics and Automation Letters*, **2018**
- [10] S. E. Naghibi, S. Karabasov, M. A. Jalali, **S.M.H. Sadati**, "Fast spectral solutions of the double-gyre problem in a turbulent flow regime." *Applied Mathematical Modelling*, **2018**
- [11] **S.M.Hadi Sadati**, S. Elnaz Naghibi, Ali Shiva, Yohan Noh, Aditya Gupta, Ian D. Walker, Kaspar Althoefer, Thrishantha Nanayakkara. "A geometry deformation model for braided continuum manipulators." *Frontiers in Robotics and AI*, **2017**
- [12] **S.M.Hadi Sadati**, M. Naraghi, A. R. Ohadi Hamedani; "Optimum Design, Build and Experiment of a Passive Walking Biped: Effects of Structural Parameters on Efficiency, Stability and Robustness on Uneven Trains." *Modares Mechanical Engineering Journal*, vol. 12, No. 6, pp. 52-68 (in Persian), **2012**

Book Chapter

- [13] D Guevara Mosquera, **S.M.H. Sadati**, KA Althoefer, T Nanayakkara, "Smart Hydrogel for Stiffness Controllable Continuum Manipulators: A Conceptual Design", *Soft and Stiffness-controllable Robotics Solutions for Minimally Invasive Surgery: The STIFFFLOP Approach*, River Publishers Series in Automation, Control and Robotics, Denmark, ISBN: 9788793519725, **2018**

Peer-Reviewed Conference Articles

- [14] Kayode Sonaike and **S.M.Hadi Sadati**, Christos Bergeles, Ian D. Walker, "Exploiting the Morphology of a Shape Memory Spring as the Active Backbone of a Highly Dexterous Tendril Robot (ATBR)", IEEE International Conference on Intelligent Robots and Systems (IROS), **2020**
- [15] **S.M.Hadi Sadati**, Steffen Zschaler, Christos Bergeles, "A Matlab-Internal DSL for Modelling Hybrid Rigid-Continuum Robots with TMTDyn.", 6th Workshop on Model-Driven Robot Software Engineering (MORSE) Munich, Germany, **2019**
- [16] **S.M.H. Sadati**, A. Shiva, S. E. Naghibi, C. Rucker, C. Bergeles, L. Renson, K. Althoefer, T. Nanayakkara, H. Hauser and I. Walker., "Reduced Order vs. Discretized Lumped System Models for Continuum Manipulators: New Methods and a Comparative Study Based on Experiments." Robotics, Science and Systems (RSS) Conference, Freiburg, Germany, **2019**
- [17] **S.M.H. Sadati**, W Thomas, "Toward Computing with Spider Webs: Computational Setup Realization", Living Machines Conference (LM 2018), Paris, France, **2018**
- [18] **S.M.H. Sadati**, S. E. Naghibi, K. Althoefer, T. Nanayakkara, "Toward a Low Hysteresis Helical Scale Jamming Interface Inspired by Teleost Fish Scale Morphology and Arrangement", IEEE International Conference on Soft Robotics (RoboSoft 2018), Livorno, Italy, **2018**
- [19] **S.M.H. Sadati**, A. Meghdari, "Singularity-Free Planning for a Robot Cat Free-Fall with Control Delay: Role of Limbs and Tail", Int. Conference on Mechanical and Aerospace Engineering (ICMAE), IEEE, (Winner of Excellent Oral Presentation Award in Robot System Design and Control Session), **2017**
- [20] **S.M.H. Sadati**, S. E. Naghibi, A. Shiva, I. D. Walker, K. Althoefer, T. Nanayakkara, "Continuum Manipulators Mechanics, A Comparative Study of Six Methods with Experiments", 18th Towards Autonomous Robotic Systems (TAROS), **2017**
- [21] H. Afrisal and **S.M.H. Sadati**, T. Nanayakkara, "A Bio-Inspired Electro-Active Velcro Mechanism Using Shape Memory Alloy for Wearable and Stiffness Controllable Layers", Information and Automation for Sustainability (ICIAfS), 2016, 9th International Conference on. IEEE, **2016**
- [22] **S.M.H. Sadati**, A. Shiva, A. Ataka, S. E. Naghibi, I. D Walker, K. Althoefer, T. Nanayakkara, "A Geometry Deformation Model for Compound Continuum Manipulators with External Loading", IEEE Int. Conference on Robotics and Automation (ICRA), **2016**
- [23] **S.M.H. Sadati**, Y. Noh, S. E. Naghibi, K. Althoefer, T. Nanayakkara, "Stiffness Control of Soft Robotic Manipulator for Minimally Invasive Surgery (MIS) Using Scale Jamming". Intelligent Robotic and Applications, Springer., **2015**
- [24] **S.M.H. Sadati**, S. E. Naghibi, M. Naraghi. "An Automatic Algorithm to Derive Linear Vector Form of Lagrangian Equation of Motion with Collision and Constraint." Procedia Computer Sci. 76:217-222., **2015**
- [25] M. Zheng, **S.M.H. Sadati**, P. Ghalamchi, T. Nanayakkara, "Passive dynamics of high frequency bat wing flapping with an anisotropic membrane." Information and Automation for Sustainability (ICIAfS), 7th Int. Conf. on. IEEE. (Winner of Best Student Paper Award), **2014**
- [26] Ali Meghdari, **S.M.Hadi Sadati**, " Cat Landing on Rigid and Flexible Surfaces: Semi-Flat Multi Impact Modeling and Path Planning in Presence of Constraints." Advances in Nano, Biomechanics, Robotics, and Energy Research (ANBRE13). Int' l Assoc. of Structural Engineering & Mechanics (IASEM), **2013**
- [27] **S.M.H. Sadati**, M. Borgheinejad, H. Fooladi, M. Naraghi, A. R. Ohadi Hamedani, "Optimum Design, Manufacturing and Experiment of a Passive Walking Biped: Effects of Structural Parameters on Efficiency, Stability and Robustness on Uneven Trains." Applied Mechanics and Materials. Vol. 307. Trans Tech Publications, **2013**

- [28] **S.M.H. Sadati**, M. Ghasimi, M. A. Abbaspour, "Analysis, Modeling, and Optimization of Tooth Modification in High Speed Helical Gears", 5th Annual Conference on Rotating Equipment in Oil and Power Industries, Rotating Equipment 2014, Tehran, Iran, January 21-22, (Poster presentation, in Persian), **2012**
- [29] R. Sharifi, H. Ghariblou, **S.M.H. Sadati**, "Dynamical Modeling and Optimization of Movement for a Cable Driven Base Robotic Arm Manipulator in an Environment with Obstacles", The Int. Conf. on Mech. Eng. & Adv. Tech. (ICMEAT 2012), Isfahan, Iran (in Persian), **2012**
- [30] **S.M.H. Sadati**, M. Naraghi, A. R. Ohadi Hamedani, "Analysis and Optimization of a passive Walking Biped", 19th Annual Conf. on Mech. Eng. in Iran, ISME 2011, Birjand, Iran, (in Persian), **2011**
- [31] **S.M.H. Sadati**, A. R. Ohadi Hamedani, M. Naraghi, "Design and Build of a Biped Passive Walker: Investigating the Effects of Structural Parameters on Performance, Efficiency and Gait Stability", 19th Annual Conf. on Mech. Eng. in Iran, ISME 2011, Birjand, Iran (in Persian), **2011**

Workshop Proposals

- [32] T. G. Thuruthel, C. Della Santina, **S.M.H. Sadati**, F. Renda, C. Laschi, "[Application-Oriented Modelling and Control of Soft Robots](#)", IEEE International Conference on Intelligent Robots and Systems (IROS), **2020**

Workshop & Symposium Articles

- [33] ASAME robotic team members and **S.M.H. Sadati**, "ASAME 3: Team Description Paper", RoboCup World Competition, Singapore, Singapore, **2010**
- [34] ASAME robotic team members and **S.M.H. Sadati**, "ASAME 2: Team Description Paper", Int. Robotic Festival, Iran Open, Tehran, Iran (in Persian), **2010**
- [35] ASAME robotic team members and **S.M.H. Sadati**, "ASAME 2: Team Description Paper", RoboCup World Competition, Graz, Austria (Winner of the 4th Place in Best Manipulator Design Technical Challenge), **2010**
- [36] ASAME robotic team members and **S.M.H. Sadati**, "ASAME 1: Team Description Paper", Int. Robotic Festival, Iran Open, Qazvin, Iran (in Persian – Winner of the 4th Place in Real Rescue Robot League), **2010**