

Europass Curriculum Vitae



Personal information

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Sabattini Lorenzo

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Italian

March 26th, 1983

Male

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Short bio

Lorenzo Sabattini is an Assistant Professor at the Department of Sciences and Methods for Engineering, University of Modena and Reggio Emilia, Italy (since 2012).

He received his B.Sc. and M.Sc. in Mechatronic Engineering from the University of Modena and Reggio Emilia (Italy) in 2005 and 2007 respectively, and his Ph.D. in Control Systems and Operational Research from the University of Bologna (Italy) in 2012. In 2010 he has been a Visiting Researcher at the University of Maryland, College Park, MD (USA). In 2012 he has been a Postdoctoral Researcher at the University of Modena and Reggio Emilia. His main research interests include multi-robot systems, decentralized estimation and control, and mobile robotics.

He is one of the founding co-chairs of the IEEE RAS Technical Committee on Multi-Robot Systems: he has served as the corresponding co-chair since its foundation, in 2014.

He has served as a Guest Editor for the Special Issue on Networked Cooperative Autonomous Systems of the IEEE Transactions on Automation Science and Engineering (T-ASE), in 2014. Since 2014, he has been appointed as Associate Editor for InTech IJARS (Topic: Mobile Robots and Multi-Robot Systems). Since 2015, he has been appointed as Associate Editor for the IEEE Robotics and Automation Letters (RA-L).

He has been serving as Associate Editor for IEEE ICRA 2015 and 2016, and IEEE/RSJ IROS 2015. He is member of the Program Committee of the IRMAS track of ACM/SIGAPP SAC 2015 and 2016, and of RSS 2015.

He co-organized workshops on Multi-Robot Systems at IEEE ICRA 2013, ICRA 2014, IROS 2014, RSS 2015, IROS 2015 and a workshop on Robotics and Logistics at ERF 2014.

Position

Dates

Position

Main topics

Institution

December 2012 – today

Assistant Professor (Ricercatore)

Decentralized control of multi robot systems, and industrial applications of mobile robotics

University of Modena e Reggio Emilia

Teaching

Dates	2011– today
Course	Digital Control
Program	Master's Degree course in Mechatronic Engineering
Institution	<i>Department of Engineering Sciences and Methods – DISMI (Reggio Emilia). University of Modena and Reggio Emilia</i>

Education and Previous Academic Experience

Dates	January 2012 – November 2012
Position	Post–doc research fellow
Main topics	Developments of control algorithms for multi robot systems
Institution	<i>University of Modena e Reggio Emilia</i>
Dates	January 2009 – April 2012
Certificate or diploma	PhD in Control Systems and Operational Research , (financed with scholarship)
Thesis	Nonlinear Control Strategies for Cooperative Control of Multi–Robot Systems
Main topics	Automation, mobile robotics, multi robot systems
Institution	<i>Alma Mater Studiorum – University of Bologna</i>
Dates	March 2010 – September 2010
Position	Visiting student
Main topics	Control of multi robot systems, development of distributed coordination algorithms. Supervisor: Dr. Nikhil Chopra
Institution	<i>University of Maryland, College Park (MD), USA</i>
Dates	April 2008 – December 2008
Position	Research fellow
Main topics	Developments of control algorithms for multi robot systems
Institution	<i>University of Modena e Reggio Emilia</i>
Dates	December 2007
Certificate or diploma	Engineering professional degree
Dates	October 2005 – October 2007
Certificate or diploma	Master's Degree in Mechatronic Engineering
Thesis	Development and experimental validation of algorithms for the formation control of mobile robots (in Italian: Sviluppo e verifica sperimentale di algoritmi di controllo di formazione per robot mobili)
Mark	110/110 summa cum laude
Institution	<i>University of Modena e Reggio Emilia</i>
Dates	October 2002 – October 2005
Certificate or diploma	Bachelor's Degree in Mechatronic Engineering

Thesis	Development of early warning algorithms to identify the actual gear ratio on board and recognition of faults in the related sensors (in Italian: Implementazione di algoritmi early warning di identificazione dei reali rapporti di trasmissione a bordo veicolo e riconoscimento malfunzionamenti della sensoristica relativa)
Mark	110/110 summa cum laude
Institution	University of Modena e Reggio Emilia

Scientific publications

International journals	<p>[1] V. Digani, L. Sabattini, and C. Secchi. A probabilistic eulerian traffic model for the coordination of multiple agvs in automatic warehouses. <i>IEEE Robotics and Automation Letters</i>, 1(1):26–32, jan. 2016</p> <p>[2] L. Sabattini, C. Secchi, M. Cocetti, A. Levratti, and C. Fantuzzi. Implementation of coordinated complex dynamic behaviors in multi-robot systems. <i>IEEE Transactions on Robotics</i>, 31(4):1018–1032, aug. 2015</p> <p>[3] V. Digani, L. Sabattini, C. Secchi, and C. Fantuzzi. Ensemble coordination approach in multi-agv systems applied to industrial warehouses. <i>IEEE Transactions on Automation Science and Engineering</i>, 12(3):922–934, jul. 2015</p> <p>[4] L. Sabattini, F. Ehlers, and D. Sofge. Guest editorial special issue on networked cooperative autonomous systems. <i>IEEE Transactions on Automation Science and Engineering</i>, 12(3):783 – 785, jul. 2015</p> <p>[5] L. Sabattini, C. Secchi, and N. Chopra. Decentralized estimation and control for preserving the strong connectivity of directed graphs. <i>IEEE Transactions on Cybernetics</i>, 45(10):2273–2286, oct. 2015</p> <p>[6] R. Falconi, L. Sabattini, C. Secchi, C. Fantuzzi, and C. Melchiorri. Edge-weighted consensus based formation control strategy with collision avoidance. <i>Robotica</i>, 33(02):332–347, February 2015</p> <p>[7] L. Sabattini, C. Secchi, and N. Chopra. Decentralized connectivity maintenance for networked lagrangian dynamical systems with collision avoidance. <i>Asian Journal of Control (Invited Paper)</i>, 17(1):111–123, January 2015</p> <p>[8] L. Sabattini, N. Chopra, and C. Secchi. Decentralized connectivity maintenance for cooperative control of mobile robotic systems. <i>The International Journal of Robotics Research (SAGE)</i>, 32(12):1411–1423, October 2013</p> <p>[9] L. Sabattini, C. Secchi, N. Chopra, and A. Gasparri. Distributed control of multi-robot systems with global connectivity maintenance. <i>IEEE Transactions on Robotics</i>, 29(5):1326–1332, October 2013</p> <p>[10] C. Secchi, L. Sabattini, and C. Fantuzzi. Decentralized global connectivity maintenance for interconnected lagrangian systems in the presence of data corruption. <i>European Journal of Control</i>, 19(6):461–468, December 2013</p> <p>[11] L. Sabattini, C. Secchi, and C. Fantuzzi. Closed-curve path tracking for decentralized systems of multiple mobile robots. <i>Journal of Intelligent and Robotic Systems (Springer)</i>, 71(1):109–123, 2013</p> <p>[12] L. Sabattini, C. Secchi, and C. Fantuzzi. Arbitrarily shaped formations of mobile robots: artificial potential fields and coordinate transformation. <i>Autonomous Robots (Springer)</i>, 30(4):385–397, may 2011</p>
International conferences	<p>[13] L. Sabattini, C. Secchi, and C. Fantuzzi. Eigenvalue placement for asymptotic stability in piecewise linear switched systems. In <i>Proceedings of the IEEE Conference on Decision and Control (CDC)</i>, pages 4885–4890, Osaka, Japan, dec. 2015</p>

- [14] F. Boem, L. Sabattini, and C. Secchi. Decentralized state estimation for heterogeneous multi-agent systems. In *Proceedings of the IEEE Conference on Decision and Control (CDC)*, pages 4121–4126, Osaka, Japan, dec. 2015
- [15] L. Sabattini, C. Secchi, A. Levratti, M. Cocetti, and C. Fantuzzi. Coordinated dynamic behaviors in multi-robot systems with time-varying topologies. In *Proceedings of the IEEE Conference on Decision and Control (CDC)*, pages 6190–6195, Osaka, Japan, dec. 2015
- [16] E. Cardarelli, L. Sabattini, C. Secchi, and C. Fantuzzi. Cloud robotics paradigm for enhanced navigation of autonomous vehicles in real world industrial applications. In *Proceedings of the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, sep.-oct. 2015
- [17] C. Secchi, L. Sabattini, and C. Fantuzzi. Conducting multi-robot systems: gestures for the passive teleoperation of multiple slaves. In *Proceedings of the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, sep.-oct. 2015
- [18] E. Cardarelli, L. Sabattini, V. Digani, C. Secchi, and C. Fantuzzi. Interacting with a multi AGV system. In *Proceedings of the IEEE International Conference on Intelligent Computer Communication and Processing (ICCP)*, Cluj-Napoca, Romania, sep. 2015
- [19] F. Oleari, M. Magnani, D. Ronzoni, L. Sabattini, E. Cardarelli, V. Digani, C. Secchi, and C. Fantuzzi. Improving AGV systems: Integration of advanced sensing and control technologies. In *Proceedings of the IEEE International Conference on Intelligent Computer Communication and Processing (ICCP)*, Cluj-Napoca, Romania, sep. 2015
- [20] C. Ghedini, C. Secchi, C. H. C. Ribeiro, and L. Sabattini. Improving robustness in multi-robot networks. In *Proceedings of the IFAC Symposium on Robot Control (SYROCO)*, Salvador, Brazil, aug. 2015
- [21] L. Sabattini, V. Digani, M. Lucchi, C. Secchi, and C. Fantuzzi. Mission assignment for multi-vehicle systems in industrial environments. In *Proceedings of the IFAC Symposium on Robot Control (SYROCO)*, Salvador, Brazil, aug. 2015
- [22] L. Sabattini, C. Secchi, A. Levratti, and C. Fantuzzi. Decentralized control of cooperative robotic systems for arbitrary setpoint tracking while avoiding collisions. In *Proceedings of the IFAC Symposium on Robot Control (SYROCO)*, Salvador, Brazil, aug. 2015
- [23] L. Sabattini, E. Cardarelli, V. Digani, C. Secchi, C. Fantuzzi, and K. Furstenberg. Advanced sensing and control techniques for multi agv systems in shared industrial environments. In *Proceedings of the IEEE International Conference on Emerging Technologies and Factory Automation (ETFA)*, Luxembourg, sep. 2015
- [24] V. Digani, M. A. Hsieh, L. Sabattini, and C. Secchi. A quadratic programming approach for coordinating multi-agv systems. In *Proceedings of the IEEE International Conference on Automation Science and Engineering (CASE)*, Gothenburg, Sweden, aug. 2015
- [25] C. Secchi, L. Sabattini, and C. Fantuzzi. Port-hamiltonian based teleoperation of a multi-robot system on periodic trajectories. In *Proceedings of the IFAC Workshop on Lagrangian and Hamiltonian Methods for Non Linear Control (LHMNLC)*, Lyon, France, jul. 2015
- [26] L. Sabattini, C. Secchi, and C. Fantuzzi. Cooperative dynamic behaviors in networked systems with decentralized state estimation. In *Proceedings of the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, Chicago, IL, USA, sep. 2014
- [27] V. Digani, L. Sabattini, C. Secchi, and C. Fantuzzi. An automatic approach for the generation of the roadmap for multi-agv systems in an industrial environment. In *Proceedings of the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, Chicago, IL, USA, sep. 2014

- [28] V. Digani, F. Caramaschi, L. Sabattini, C. Secchi, and C. Fantuzzi. Obstacle avoidance for industrial AGVs. In *Proceedings of the IEEE International Conference on Intelligent Computer Communication and Processing (ICCP)*, pages 227 – 232, Cluj-Napoca, Romania, sep. 2014
- [29] E. Cardarelli, L. Sabattini, C. Secchi, and C. Fantuzzi. Multisensor data fusion for obstacle detection in automated factory logistics. In *Proceedings of the IEEE International Conference on Intelligent Computer Communication and Processing (ICCP)*, pages 221 – 226, Cluj-Napoca, Romania, sep. 2014
- [30] F. Oleari, M. Magnani, D. Ronzoni, and L. Sabattini. Industrial AGVs: Toward a pervasive diffusion in modern factory warehouses. In *Proceedings of the IEEE International Conference on Intelligent Computer Communication and Processing (ICCP)*, pages 233 – 238, Cluj-Napoca, Romania, sep. 2014
- [31] L. Sabattini, C. Secchi, and C. Fantuzzi. Controllability and observability preservation for networked systems with time varying topologies. In *Proceedings of the IFAC World Congress*, pages 1837 – 1842, Cape Town, South Africa, aug. 2014
- [32] L. Sabattini, C. Secchi, M. Cocetti, and C. Fantuzzi. Implementation of arbitrary periodic dynamic behaviors in networked systems. In *Proceedings of the IEEE International Conference on Robotics and Automation (ICRA)*, Hong Kong, China, jun. 2014
- [33] V. Digani, L. Sabattini, C. Secchi, and C. Fantuzzi. Hierarchical traffic control for partially decentralized coordination of multi agv systems in industrial environments. In *Proceedings of the IEEE International Conference on Robotics and Automation (ICRA)*, Hong Kong, China, jun. 2014
- [34] A. Gasparri, A. Leccese, L. Sabattini, and G. Ulivi. Collective control objective and connectivity preservation for multi-robot systems with bounded input. In *Proceedings of the American Control Conference (ACC)*, Portland, OR, USA, jun. 2014
- [35] M. Cocetti, L. Sabattini, C. Secchi, and C. Fantuzzi. Decentralized control strategy for the implementation of cooperative dynamic behaviors in networked systems. In *Proceedings of the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, pages 5902 – 5907, Tokyo, Japan, nov. 2013
- [36] V. Digani, L. Sabattini, C. Secchi, and C. Fantuzzi. Towards decentralized coordination of multi robot systems in industrial environments: a hierarchical traffic control strategy. In *Proceedings of the IEEE International Conference on Intelligent Computer Communication and Processing (ICCP)*, Cluj-Napoca, Romania, sep. 2013
- [37] L. Sabattini, V. Digani, C. Secchi, G. Cotena, D. Ronzoni, M. Foppoli, and F. Oleari. Technological roadmap to boost the introduction of agvs in industrial applications. In *Proceedings of the IEEE International Conference on Intelligent Computer Communication and Processing (ICCP)*, Cluj-Napoca, Romania, sep. 2013
- [38] L. Sabattini, C. Secchi, and C. Fantuzzi. Collision avoidance using gyroscopic forces for cooperative lagrangian dynamical systems. In *Proceedings of the IEEE International Conference on Robotics and Automation (ICRA)*, pages 945–950, Karlsruhe, Germany, may 2013
- [39] L. Sabattini, C. Secchi, and N. Chopra. Decentralized control for maintenance of strong connectivity for directed graphs. In *Proceedings of the IEEE Mediterranean Conference on Control and Automation (MED)*, Platania-Chania, Crete - Greece, jun. 2013
- [40] L. Sabattini, A. Levratti, F. Venturi, E. Amplo, C. Fantuzzi, and C. Secchi. Experimental comparison of 3d vision sensors for mobile robot localization for industrial application: stereo-camera and RGB-D sensor. In *Proceedings of the IEEE International Conference on Control, Automation, Robotics and Vision (ICARCV)*, Guangzhou, China, dec. 2012

- [41] C. Secchi, L. Sabattini, and C. Fantuzzi. Decentralized global connectivity maintenance for interconnected lagrangian systems with communication delays. In *Proceedings of the IFAC Workshop on Lagrangian and Hamiltonian Methods for Non Linear Control (LHMNLC)*, Bertinoro, Italy, aug. 2012
- [42] L. Sabattini, A. Gasparri, C. Secchi, and N. Chopra. Enhanced connectivity maintenance for multi-robot systems. In *Proceedings of the IFAC Symposium on Robot Control (SYROCO)*, Dubrovnik, Croatia, sep. 2012
- [43] L. Sabattini, C. Secchi, and N. Chopra. Decentralized connectivity maintenance for networked lagrangian dynamical systems. In *Proceedings of the IEEE International Conference on Robotics and Automation (ICRA)*, pages 2433–2438, St. Paul, MN, USA, may 2012
- [44] L. Sabattini, N. Chopra, and C. Secchi. On decentralized connectivity maintenance for mobile robotic systems. In *Proceedings of the IEEE Conference on Decision and Control (CDC)*, pages 988–993, Orlando, FL, USA, dec. 2011
- [45] L. Sabattini, N. Chopra, and C. Secchi. Distributed control of multi-robot systems with global connectivity maintenance. In *Intelligent Robots and Systems (IROS), 2011 IEEE/RSJ International Conference on*, pages 2321–2326, San Francisco, CA, USA, sept. 2011
- [46] R. Falconi, L. Sabattini, C. Secchi, C. Fantuzzi, and C. Melchiorri. A graph-based collision-free distributed formation control strategy. In *Proceedings of the IFAC World Congress*, volume 18, Milano, Italy, 2011
- [47] L. Sabattini, C. Secchi, C. Fantuzzi, and D. de Macedo Possamai. Tracking of closed-curve trajectories for multi-robot systems. In *Intelligent Robots and Systems (IROS), 2010 IEEE/RSJ International Conference on*, pages 6089–6094, Taipei, Taiwan, oct. 2010
- [48] L. Sabattini, C. Secchi, C. Fantuzzi, and A. Stefani. Bird's-eye view image for the localization of a mobile robot by means of trilateration. In *Proceedings of the IFAC Symposium on Intelligent Autonomous Vehicles (IAV)*, volume 7, Lecce, Italy, 2010
- [49] L. Sabattini, C. Secchi, and C. Fantuzzi. Potential based control strategy for arbitrary shape formations of mobile robots. In *Intelligent Robots and Systems, 2009 (IROS). IEEE/RSJ International Conference on*, pages 3762–3767, St. Louis, MO, USA, oct. 2009

Book chapters

- [50] L. Sabattini, E. Cardarelli, V. Digani, C. Secchi, and C. Fantuzzi. Multi agv systems in shared industrial environments: Advanced sensing and control techniques for enhanced safety and improved efficiency. In E. Messina, editor, *STP1594 on Autonomous Industrial Vehicles: From the Laboratory to the Factory Floor*. ASTM Selected Technical Papers, 2015. (in press)
- [51] L. Sabattini, C. Secchi, and C. Melchiorri. Network robotics. In R. Tempo and M. Indri, editors, *Handbook on Electrical Engineering Technology and Systems*. CRC Press/Taylor & Francis, 2015. (in press)

Contributions to international workshops and symposia

- [52] F. Ehlers, L. Sabattini, and D. Sofge. Coordination design. Workshop on Principles of Multi-Robot Systems, held at Robotics: Science and Systems (RSS), jul. 2015. Rome, Italy
- [53] L. Sabattini, E. Cardarelli, V. Digani, C. Secchi, and C. Fantuzzi. Multi agv systems in shared industrial environments: Advanced sensing and control techniques for enhanced safety and improved efficiency. Workshop on Autonomous Industrial Vehicles: From the Laboratory to the Factory Floor, held at the IEEE International Conference on Robotics and Automation (ICRA), may 2015. Seattle, WA, USA
- [54] L. Sabattini and C. Secchi. Cooperative dynamic behaviors in heterogeneous multi-robot systems. Workshop on Taxonomies of Interconnected Systems: Asymmetric Interactions in Distributed Robotics, held at the IEEE International Conference on Robotics and Automation (ICRA), may 2015. Seattle, WA, USA

[55] L. Sabattini. Decentralized connectivity maintenance for multi-robot systems. Workshop on Taxonomies of Interconnected Systems: Topology in Distributed Robotics, held at the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS) - Invited talk, sep. 2014. Chicago, IL, USA

[56] C. Secchi, L. Sabattini, and C. Fantuzzi. Multimodal passivity based teleoperation of multiple slaves. Workshop on Telerobotics for Real-Life Applications: Opportunities, Challenges, and New Developments, held at the IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), sep. 2014. Chicago, IL, USA

[57] L. Sabattini. Decentralized control of networked systems for setpoint tracking. Workshop on Crossing the Reality Gap: Control, Human Interaction and Cloud Technology for Multi- and Many- Robot Systems, held at the IEEE International Conference on Robotics and Automation (ICRA) - Invited talk, jun. 2014. Hong Kong, China

[58] V. Digani, L. Sabattini, C. Secchi, and C. Fantuzzi. Decentralized coordination enhanced by centralized information: multiple agvs in industrial application. Workshop On the Centrality of Decentralization in Multi-robot Systems: Holy Grail or False Idol?, held at the IEEE International Conference on Robotics and Automation (ICRA), jun. 2014. Hong Kong, China

[59] L. Sabattini. On multi-agv systems for factory logistics: the pan-robots project. Workshop on Autonomous Vehicles for Long-Term Operation in Industrial Environments, euRobotics Forum (ERF) - Invited talk, mar. 2014. Rovereto, Italy

[60] V. Digani, L. Sabattini, C. Secchi, and C. Fantuzzi. Hierarchical traffic control for partially decentralized coordination of multi agv systems in industrial environments. Proceedings of the Workshop on Planning, Perception and Navigation for Intelligent Vehicles (PPNIV), IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), nov. 2013. Tokyo, Japan

[61] L. Sabattini. Multi-AGV systems for factory logistics. Workshop on Crossing the Reality Gap - From Single to Multi- to Many Robot Systems, held at the IEEE International Conference on Robotics and Automation (ICRA) - Invited talk, may 2013. Karlsruhe, Germany

[62] L. Sabattini, C. Secchi, M. Cocetti, and C. Fantuzzi. Implementation of cooperative dynamic behaviors in networked systems with controllability preservation. Proceedings of the Workshop on Towards Fully Decentralized Multi-Robot Systems: Hardware, Software and Integration, held at the IEEE International Conference on Robotics and Automation (ICRA), may 2013. Karlsruhe, Germany

Italian conferences

[63] L. Sabattini, C. Secchi, and C. Fantuzzi. Tracking of complex trajectories for leader-follower multi-robot systems. AUTOMATICA.IT Congress, 2014. Bergamo, Italy

[64] L. Sabattini, C. Secchi, C. Fantuzzi, N. Chopra, and A. Gasparri. Distributed global connectivity maintenance for multi-robot systems. AUTOMATICA.IT Congress, 2012. Benevento, Italy

[65] L. Sabattini, C. Secchi, and C. Fantuzzi. Potential based control strategy for arbitrary shape formations of mobile robots. SIDRA Congress (Poster), 2009. Siracusa, Italy

[66] L. Sabattini, C. Secchi, and C. Fantuzzi. Formation control and obstacle avoidance. SIDRA Congress (Poster), 2008. Vicenza, Italy

PhD thesis

[67] L. Sabattini. *Nonlinear Control Strategies for Cooperative Control of Multi-Robot Systems*. PhD thesis, Alma Mater Studiorum – Università di Bologna, Bologna, Italy, 2012

Editorial activity

Journals

Date	2015 - today Associate Editor for the IEEE Robotics and Automation Letters (RA-L)
Date	2015 - today Review Editor for Frontiers in Robotics and AI
Date	2014 - today Associate Editor for the InTech International Journal of Advanced Robotic Systems (IJARS. Topic: Mobile Robots and Multi-Robot Systems)
Date	2014 - 2015 Lead Guest Editor for the Special Issue on Networked Cooperative Autonomous System of the IEEE Transactions on Automation Science and Engineering (T-ASE)

Conferences

Date	2016 Associate Editor for IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS) 2016
Date	2016 Member of the Program Committee of the International Symposium on Distributed Autonomous Robotic Systems (DARS) 2016
Date	2016 Associate Editor for IEEE International Conference on Robotics and Automation (ICRA) 2016
Date	2015 Member of the Program Committee of the Intelligent Robotics and Multi-Agent Systems (IRMAS) track of ACM/SIGAPP Symposium on Applied Computing (SAC) 2016
Date	2015 Associate Editor for IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS) 2015
Date	2015 Associate Editor for IEEE International Conference on Robotics and Automation (ICRA) 2015
Date	2015 Member of the Program Committee of the Robotics Science and Systems (RSS) 2015
Date	2014 Member of the Program Committee of the Intelligent Robotics and Multi-Agent Systems (IRMAS) track of ACM/SIGAPP Symposium on Applied Computing (SAC) 2015

Organization of scientific events

Date	2016 Co-organizer of the IEEE RAS Summer School on Multi-Robot Systems
Date	2016 Co-organizer of the ICRA 2016 Workshop Fielded multi-robot systems operating on land, sea, and air
Date	2016 Co-organizer of the IV 2016 Workshop Cooperative autonomous intelligent vehicles are advanced robotic systems of systems: current trends and challenges
Date	2015

Date	2015	Co-organizer of the IROS 2015 Workshop Cooperative vehicles and robotic systems for industrial applications
Date	2014	Co-organizer of the RSS 2015 Workshop Principles of Multi-Robot Systems
Date	2014	Co-organizer of the IROS 2014 Workshop The future of multiple-robot research and its multiple identities
Date	2014	Co-organizer of the ICRA 2014 Workshop Crossing the Reality Gap: Control, Human Interaction and Cloud Technology for Multi- and Many- Robot Systems
Date	2014	Co-organizer of the ERF 2014 Workshop Advanced Robotics for Industrial Logistics
Date	2013	Co-organizer of the ICRA 2013 Workshop Crossing the Reality Gap - From Single to Multi- to Many Robot Systems

Service for Scientific Societies

Date	2014 - Today	L. Sabattini is one of the founders, together with A. Franchi (LAAS-CNRS, France) and N. Ayanian (Univ. of Southern California, USA) of the Technical Committee on Multi-Robot Systems, within the IEEE Robotics and Automation Society. Since its foundation, he is serving as the Corresponding Co-Chair
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Memberships of Scientific Societies

Date	2014 - Today	Funding Co-Chair, and Corresponding Co-Chair, IEEE/RAS Technical Committee on Multi-Robot Systems
Date	2012 - Today	Member, IEEE/RAS Technical Committee on Networked Robots
Date	2008 - Today	Member, IEEE
Date	2008 - Today	Member, IEEE Robotics and Automation Society (RAS)
Date	2008 - Today	Member, IEEE Control System Society (CSS)
Date	2015	Member of the Triennial Review Committee for the Technical Committees of the IEEE Robotics and Automation Society