

MATTHEW KELLY

(845) · 594 · 1517 ◊ matthew.kelly2@gmail.com
8 Green Street ◊ Watertown, MA 02472

EDUCATION

- Cornell University**, Ithaca NY - GPA 3.85
Ph.D. Mechanical Engineering (**minor:** Computer Science) *May 2016*
M.S. Mechanical Engineering *August 2014*
Award: National Science Foundation Graduate Fellowship
- Tufts University**, Medford MA - GPA 3.97
B.S. Mechanical Engineering (**minor:** Music) *May 2011*
Summa Cum Laude with Highest Thesis Honors
Awards: Mechanical Engineering Prize, Benjamin G. Brown Scholarship
- University of Canterbury**, Christchurch, New Zealand
Study abroad program in Mechanical Engineering *July - November 2009*

RESEARCH & WORK EXPERIENCE

- Rethink Robotics** *Senior Robotics Engineer* June 2016 - present
Boston, MA
- Designed and implemented the algorithms that are used for trajectory generation on the Sawyer robot arm. These methods run in real-time and are used for both joint and end-effector motions. (C++)
 - Implemented motion testing and analysis framework, some of which is open source. (ROS and Python)
- Cornell Biorobotics and Locomotion Lab** *Ph.D. Research, Advisor: Andy Ruina* November 2011 - May 2016
Ithaca, NY
- Designed and implemented robust walking controllers for the Cornell Ranger robot.
 - Wrote an open source trajectory optimization library: <https://github.com/MatthewPeterKelly/OptimTraj>
 - Developed my own simulation code for the Cornell Ranger walking robot
 - Designed non-linear controllers for simple models of walking using variations on genetic algorithms, dynamic programming, and trajectory libraries.
 - Website: www.matthwepeterkelly.com It includes an overview of my research and publications, several tutorials, and links to my open-source code on GitHub and Matlab file exchange.
- Tufts Biomechanical Engineering Lab** *Advisor: Thomas James* November 2009 - August 2011
Medford, MA
- Design, fabrication, and testing of a novel sagittal bone saw.
 - Results: two proptotype saws and a test fixture, 400 hours of machine shop work, two full experiments, a conference presentation, journal publication, and a U.S. patent.
- MIT Non-Newtonian Fluids Lab** *Advisor: Gareth McKinley (MIT), Chris Rogers (Tufts)* January 2011 - August 2011
Cambridge, MA
- Non-linear control design and implementation on a filament-stretching rheometer (FiSER).
 - Software: programmed a GUI in LabVIEW as well as real-time data acquisition, analysis, and control.
 - Hardware: National Instruments cRIO and FPGA.

TEACHING EXPERIENCE

Head Teaching Assistant: Dynamics

Cornell University, Spring 2013 & 2016

- Managed 12 teaching staff and organized 180 students.
- Taught recitation and interactive problem solving sessions.

Teaching Assistant: Mechatronics Lab

Cornell University, Fall 2012

- Lab TA working with analog circuits and microprocessors for small robots.

TECHNICAL STRENGTHS

Programming

- Linux and Windows operating systems, Git version control.
- C++, Python, Matlab, Java, LabVIEW, LaTeX.

Trajectory Optimization and Generation

- Experience implementing multiple shooting, direct collocation, and orthogonal collocation methods.
- Wrote trajectory generation code that is used on the Sawyer Robot arm, for all motion types.

Simulation

- Implemented simulations on hundreds of models, including many walking robots.
- Time-stepping and event-based contact solvers.

Control

- Markov Decision Process, dynamic programming, reinforcement learning.
- Function approximation, trajectory libraries, trajectory tracking.
- Model-based estimation: Kalman filter, EKF, UKF, particle filter.
- Genetic algorithms and heuristic optimization.

Mechanical Engineering

- Built a trebuchet with a one-ton counter-weight and 40-foot arm.
- Machine design, SolidWorks modeling.
- Machine shop: manual mill & lathe, CNC Mill.
- Woodworking and cabinetry.

PUBLICATIONS

Kelly, M. P. “An introduction to trajectory optimization: how to do your own direct collocation” Society of Industrial and Applied Mathematics Review. December 2017.

Kelly, M. P., Ruina, Andy, “Non-linear robust control for inverted-pendulum 2D walking,” International Conference on Robotics and Automation, Seattle, WA, May 26-30, 2015.

James, T. P., **Kelly, M. P.**, Lannin, Pearlman, J. J., and Saigal, A., “Sagittal Bone Saw with Orbital Blade Motion for Improved Cutting Efficiency,” Journal of Medical Devices, 2013.

PATENTS

James, T. P. and **Kelly, M. P.**, “Novel Blade Path to Introduce Impulsive Thrust Loading in Sagittal Sawing,” U.S. Patent 14/125,164, Aug 28, 2014.