

Ryan Barry

ryanbarry.me | ryanbarry.engineering@gmail.com | (315) 596-0754

Education

Rochester Institute of Technology, Rochester, NY

Master of Science in Electrical Engineering

Specialization in Robotics and AI/ML

Cumulative GPA: 3.92

Rochester Institute of Technology, Rochester, NY

Bachelor of Science in Electrical Engineering, *Summa Cum Laude*

Cumulative GPA: 3.86

Technical Skills

Languages: Assembly, C/C++, PLC Ladder Logic, Python

Libraries & Tools: CUDA, Git, Jupyter, Keras, NumPy, OpenCV, Pandas, PyTorch, ROS, Scikit-Learn, TensorFlow

Software: Altium Designer, AutoCAD, Creo, Inventor, LTSpice, MATLAB, SOLIDWORKS

Hardware: Microcontrollers, Motor/Sensor Control, PCB Design, SMT & TH Soldering, 3D Printing

Professional Experience and Research

Robotics Research Engineer II, *Robotics and Automation Design Lab*, Bryan, TX

March 2025 – Present

- Engineering fault tolerant robotic manipulators for use in contracted space missions, designed for environmental robustness and modularity.
- Designed custom PCBs in Altium for testing and spaceflight applications.
- Developed firmware and software in ROS, C++, and Python for actuator control and status monitoring.
- Built real-time data acquisition tools in C++ and Python for diagnostic logging, fault response validation, and performance analysis.

Researcher, *RIT Adaptive Human-Robot Teaming Lab*, Rochester, NY

August 2023 – May 2024

- Developed a custom reinforcement learning (RL) environment in ROS and Gazebo for terrain-aware velocity control of a quadruped robot in a physics-based simulator.
- Implemented Proximal Policy Optimization (PPO) from scratch in PyTorch with LSTM-based policy and value networks; built a custom trajectory buffer and integrated the full RL pipeline into the ROS-based system.

Robotics Graduate Teaching Assistant, *Rochester Institute of Technology*, Rochester, NY

August 2023 – May 2024

- Facilitated student learning of high-level robotics concepts and ROS through lab work and research projects.

Software Technical Lead, *RIT University Rover Challenge Team*, Rochester, NY

June 2023 – May 2024

- Spearheaded software architecture development for autonomous and remote operation of a robotic rover.
- Directed a team of engineers to develop and test software for all subsystems of RIT's rover.
- Integrated a Python-based ROS application with embedded C++ code for peripheral control via CAN.
- More at <https://ryanbarry.me/projects/robotics/rover/>

Electrical Engineer, *RIT Electric Vehicle Team*, Rochester, NY

August 2021 – May 2024

- Designed a CAN interface board for a BeagleBone Black to communicate with the network of custom electric motorcycles.
- Led a team of undergraduate electrical engineers to develop a CAN based IMU board in Altium.
- Derived and documented a full gate driver and control architecture for a 3-phase BLDC motor from first principles; mentored junior team members in implementing the full motor controller in Altium for a brushless coolant pump as a foundation for future high-power traction systems.

Machine Learning R&D Intern, *Penn State ARL*, University Park, PA

May 2023 – August 2023

- Developed proof of concept synthetic data pipeline for active acoustic ML in unmanned undersea vehicles.
- Designed Python application for scenario development and interface with UUV simulation software.
- Developed an acoustic range and angle of arrival regression model to support transfer learning hypothesis.
- More at <https://ryanbarry.me/projects/ai-ml/sonar-data-pipeline/>

Product Engineering Co-op, *The Raymond Corporation*, Greene, NY

January 2022 – July 2022

Electrical Engineering Intern, *Davis Standard LLC*, Fulton, NY

May 2021 – August 2021

Projects

Open-Source Universal Kinematic Libraries for Generic Robots

September 2023 – Present

- Developed modular C++ and Python libraries for forward and inverse kinematics of both serial-link manipulators and fixed-wheeled mobile robots.
- Enabled dynamic configuration from DH parameters or wheel layouts to support arbitrary robot topologies without rewriting core math.
- Implemented forward velocity kinematics and inverse kinematics for mobile platforms using wheel geometry
- Solved numerical inverse kinematics using Jacobian pseudo-inverse methods with tolerance-based convergence on joint angles from target end-effector pose for arbitrary robot configurations.
- More at <https://ryanbarry.me/projects/robotics/kinematics/>

Multi-Agent Reinforcement Learning for Pacman Capture the Flag

November 2023 – December 2023

- Developed a dual-agent Q-Learning RL system with custom reward shaping to coordinate offensive and defensive Pacman agents in a 2v2 Capture the Flag game.
- Engineered a shared memory mechanism for real-time inter-agent communication, enabling cooperative ambush behavior and dynamic role adaptation.
- Implemented custom learning and inference logic without external ML libraries; stored and updated network weights in a script-local dictionary.
- Trained agents via self-play and against external algorithms for generalization; reached tournament finals before final-game regression bug impacted behavior.

Air Hockey Robot

October 2023 – December 2023

- Designed a custom 3D-printed 3-DOF planar robot to play air hockey against a human via an overhead camera.
- Curated a custom dataset of over 26,000 images to train a YOLOv8 model for puck and table keypoint detection.
- Predicted puck trajectory and impact location using a linear physics model and an LSTM-based neural network, and used an inverse kinematics lookup table to intercept its path.
- More at <https://ryanbarry.me/projects/robotics/air-hockey-robot/>

Full-Stack Robot for Real-Time Object Interception

February 2023 – April 2023

- Designed and programmed a holonomic robot with real-time YOLOv8-based object tracking and trajectory alignment.
- Designed custom chassis design with 3D-printable omni wheels in SOLIDWORKS.
- Trained a custom YOLOv8 model to detect balloons and calculated their 3D velocity with a stereo camera using weighted difference method over a buffer of frames.
- Developed a ROS network for kinematic motion control and sensor integration.
- More at <https://ryanbarry.me/projects/robotics/omnidirectional-robot/>

Underwater Robot Motherboard PCB

November 2022 – April 2023

- Integrated a 7-sensor perception suite with power distribution and propulsion control on a custom PCB.
- Sensor peripherals include: 2 cameras, dissolved oxygen sensor, IMU, pH probe, salinity sensor, thermistor.
- Ethernet controller for high speed data transfer to external laptop.
- Power regulation for 11V, 5V, and 3.3V rails from a 12V nominal battery.
- High-current H-Bridge for brushed DC motor control of a propeller. Additionally a servo header for rudder control.
- Designed using Altium Designer and hand soldered SMT components.
- More at <https://ryanbarry.me/projects/electrical-engineering/underwater-robot/>

Collaborative Robot Ball-and-Cup Game

February 2023 – April 2023

- Built a ROS-based interactive game for the Baxter robot using YOLOv6 and DeepSORT with occlusion-aware ID tracking; designed a custom parallel-jaw-compatible gripper for robust cup manipulation.

Nerf Mobile Robot with Autonomous Targeting

November 2021 – December 2021

- Built a mobile robot with autonomous tracking and firing at a moving shield using a modified Nerf blaster.
- Utilized bounding box color tracking for target localization and aiming.
- Controlled trigger and flywheel with dedicated servo and logic-controlled high-side power switch.