Shrinal Thakkar

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WORK EXPERIENCE

Unity Technologies **Nov 2020– Present**

Developer, Engineering Support *Toronto, ON*

- Work with Strategy Partner Managers to help programmatic partners with t**echnical integration** into our ad network.
- Participate in client meetings as a **subject matter expert** for technical product details and **consult** on Unity exchange.
- **Investigate, research, debug, consultant, and solve integration problems**, interacting closely with programmatic partners and internal development engineers.
- Troubleshoot issues encountered by DSP partners or publishers, including but not limited to reporting discrepancies, problems with creative rendering, drops in performance, etc.
- Be the first point of contact for technical inquiries from programmatic partners.
- Collaborating with our Product and Sales teams to **build new features and bug fixes.**

EDUCATION

Lakehead University, Thunder Bay, ON, Canada.

- *Master of Science in Computer Science* ***May 2020***

Gujarat Technological University, Gujarat, India.

- *Bachelor of Engineering in Computer Engineering* ***Apr 2018***

Key-courses

- Programming Languages (Clojure), Game Programming (HaxeFlixel, Unity 3D), Digital Video Processing (Java, Python), Advanced Java(java), and Image Processing(python).

Awards

Aavishkar 2017(Innovative Ideas)

Represented my project "Tanks Multiplayer" It was the first ever and only Game project in the event. It was awarded as an innovative idea of the year across the college.

CERTIFICATIONS, SKILLS & INTERESTS

- **Skills:** C#, Java, JS, C++, C, PHP, HaxeFlixel, HTML, Clojure, CSS, Googling.
- **Game Engine:** Unreal Engine, Unity.
- **IDE /GUI Tools and Libraries:** Eclipse, Android Studio, Sublime, OpenCV, MATLAB, NetBeans.
- **Database Editors:** Oracle SQL Developer, GCP, SQL
- **Interests:** Running, Volunteering, Plants, Hiking, Mountains, Travelling, Photography, Video games,

ACADEMIC PROJECTS

3D Reconstruction. **Apr 2020**

- A system builds on Python, generating a 3D model from stereo vision.
- The system uses any regular camera, which, in the first phase, gets camera information like focal length distortions in the camera and intrinsic and extrinsic parameters of the camera for camera calibration.
- Using Semi Global Block Matching (SGBM), the system matched features.
- In phase 2, we will use those parameters to create a disparity map, and using that map, we will generate a 3D cloud.
- The disparity map will be transformed into a 3D point cloud using a transformation matrix and reprojection points.
- Using the MeshLab, we will generate the final 3D output.

More projects: Game development(Mar 2018), Tanks multiplayer, Sexual Harassment Detection.