#### Dhanush S Gowda

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# **Career Objective**

A physical design trainee to acquire advanced knowledge in my concern. Seeking a challenging career where my academic excellence will add value towards organization and personal.

# **Core Competancy**

- Through understanding on ASIC flow and practical experience on APR flow that includes Floorplanning ,Powerplanning ,placement ,CTS and Routing .
- Understanding in Various STA concepts such as Timing paths, Timing Arcs, Slack, timing constraints, PVT corners, clock Skews, Fixing timing violations, CRPR, AOCV.
- Developed a power network with no physical DRC errors and also made sure to meet the specified IR drop by varying the width ,Spacing and pitch of the metals.
- Developed an floorplan with contiguous core area, good utilization and required channel pacing with the help of flylines and data flow diagram.
- created a legalized placement block with minimal congestion, no DRC errors and no floating standard cells.
- Hands on experience on tools Synopsys IC compiler II, Synopsys Primetime.

#### **Education Details**

2025
2021
2017
2015

## **Projects worked on**

Accenture

Associate Application Developer

Client: Elevance Health Jul-2022 to Dec-2022

# Payroll Leave and absence

# **Description**

Helped in developing payroll integrations using workday and Xml an Xslt. also analysed studio integrations

#### **Tools**

Workday, Workday Studio, Oxygen XML editor

## **Challenges**

- Analysed studio integrations
- Got Certified in Workday HCM Course
- Got certified in Workday Integration

## **Domain Specific Project**

#### RV-VLSI AND EMBEDDED SYSTEMS DESIGN CENTER

Graduate Trainee Engineer

Oct-2022 to Feb-2023

# Floorplan, Power plan and placement implementation Description

Block level implementation of Lakshya subsystem: Technology 40nm, Supply Voltage 1.1V, Area 4.2 sq. mm, Power Budget-600nW, Max IR drop(VDD+VSS)-5%, No of standard cells 38403, No. of metal Layers 7

#### **Tools**

IC Compiler II Synopsys

#### **Challenges**

- Building Powerplan to maintain power network connectivity and IR Drop. Also ensuring that there were no missing vias, floating wire and power-ground DRC violations.
- Designing a Floorplan by determining Macroplacement as per the data flow diagram and using macro guidelines in order to achieve contagious core area and good utilization.
- Creating the placement block by inserting Pre placement cells, sufficient spaces in order to control the congestion and DRC violations obtained.

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## **CTS & ROUTING Implementation**

# Description

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#### **Tools**

IC Complier II- Synopsys

## **Challenges**

- Analyzing clock tree to achieve minimum insertion delay and skew. Also checked rectified for the clock DRC errors.
- Analyzing and resolving the antenna violations by inserting the metal jumper and the diode into the layout .
- Performing clock tree synthesis and optimization using classic ,CCD flows and analyzing the tools behavior by comparing the timing reports in both the flows.

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# **Analyzing the Timing Report by STA Description**

Generating of timing reports that include setup and hold slack calculations for flip flops and latch based paths working at various condition, reports and analyzed considering OCV, uncertainty CRPR, and timing exceptions (multicycle and flash paths).

# **Tools**

Primetime by Synopsys, IC Compiler II -Synopsys

### **Challenges**

- Understanding the primetime tool and commands related to the tool by analyzing their usage functionalities.
- Understanding the timing reports at every stage of PD flow, finding the cause of timing violations and how some of the violented paths are being reduced in later stages.
- Analyzing the effect of clock Skew, CRPR,OCV timing derates for all four different timing paths from the timing reports.

# **B.E / B.Tech Academic Project**

Don Bosco Institute Of Technology

# Autonomous robot navigation using LIDAR

# **Description**

This project is all about autonomous ground vehicle with lidar mounted on it This vehicle maps the environment it is placed and navigates on its own to the destination by avoiding obstacle with the help of path planning and navigation module

## **Tools**

RPLIDAR A1 360, Robotic operating system, Arduino UNO, RPI 3, DC motors, Python.

# **Challenges**

• Inaccurate Path planning so had to optimize it using better algorithms.