Foundations of Computer Science Lecture 12: Procedural Programming & Recap

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References: ML Versus Conventional Languages

- We must write !p to get the contents of p
- We write just p for the address of p
- We can store *private* reference cells in functions; simulating object oriented programming
- OCaml's assignment syntax is V := E instead of V = E
- OCaml has similar control structures: while/done, for/done and match/with
- OCaml has short syntax for updating arrays x.(1) and the access is safe against buffer overflows

What More Is There to ML?

With references, we can now make mutable linked lists



References to References

Two ways to visualize references to references:

(1) Using pointers:



(2) Using nested boxes:



Linked (Mutable) Lists

```
# type 'a mlist =
    | Nil
    | Cons of 'a * 'a mlist ref
    type 'a mlist = Nil | Cons of 'a * 'a mlist ref
```

 \rightarrow The tail can be redirected!

Linked (Mutable) Lists

 \rightarrow The tail can be redirected!

```
creates a new pointer to rest of mlist
# let rec mlistOf = function
    [] -> Nil
    [x :: 1 -> Cons (x, ref (mlistOf 1))
mlist : 'a list -> 'a mlist = <fun>
```

Extending a List to the Rear



> val extend = fn : 'a mlist ref * 'a -> 'a mlist ref

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Example of Extending a List

let mlp = ref (Nil: string mlist);;
val mlp : string mlist ref = {contents = Nil}

- # extend mlp "a";;
- : string mlist ref = {contents = Nil}

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```

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let mlp = ref (Nil : string mlist);;
val mlp : string mlist ref = {contents = Nil}

let it = extend mlp "a" ;;
val it : string mlist ref = {contents = Nil}

let it = extend it "b" ;;
- : string mlist ref = {contents = Nil}

```
# mlp ;;
- : string mlist ref =
  {contents = Cons ("a",
     {contents = Cons ("b", {contents = Nil})})}
```


ref (Cons (x, ref (Cons (y, ref Nil))))

Destructive Concatenation

```
pointing to a 'box' contents of a 'box'
# let rec joining mlp ml2 =
  match !mlp with
   Nil \rightarrow mlp := ml2
  Cons ( , mlp1) -> joining mlp1 ml2
val joining : 'a mlist ref * 'a mlist -> unit = <fun>
# let join ml1 ml2 =
  let mlp = ref ml1 in
  joining mlp ml2;
  !mlp
val join : 'a mlist -> 'a mlist -> 'a mlist = <fun>
```

Side-Effects

```
# let ml1 = mlistOf ["a"];;
val ml1 : string mlist = Cons ("a", {contents = Nil})
# let ml2 = mlistOf ["b";"c"];;
val ml2 : string mlist =
    Cons ("b", {contents = Cons ("c", {contents = Nil})})
# join ml1 ml2 ;;
```

What does this return?

Side-Effects

```
# let ml1 = mlistOf ["a"];;
val ml1 : string mlist = Cons ("a", {contents = Nil})
# let ml2 = mlistOf ["b";"c"];;
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Cons ("b", {contents = Cons ("c", {contents = Nil})})
# join ml1 ml2 ;;
```

What does this return?

```
- : string mlist =
Cons ("a",
  {contents = Cons ("b",
    {contents = Cons ("c", {contents = Nil})})
```

Functional Programming Let's Recap

Goals of Programming

- to **describe a computation** so that it can be done *mechanically*:
 - expressions compute values
 - commands cause effects
- to do so efficiently and correctly, giving right answers quickly
- to allow **easy modification** as our needs change
 - through an orderly *structure* based on *abstraction* principles
 - programmer should be able to predict effects of changes

Why Program in OCaml?

- It is interactive.
- It has a flexible notion of **data type**.
- It hides the underlying hardware: **no crashes**.
- Programs can easily be understood mathematically.
- It distinguishes naming from updating memory.
- It manages storage in memory for us.

1B Concepts in Programming Languages

1B Further Java

II Types

Execution

Upcoming Courses:

1A Operating Systems

- **1B Compiler Construction**
- 1B Programming in C/C++ 1B Concurrent & Distributed Systems

OCaml: a system

OCaml: Building Hardware Flexibility Runtime Language OCaPIC: PIC microcontrollers programmed in OCaml **Static Linking FPGAs Microcontrollers** Garbage Collect HardCaml is a structural hardware ORCONF2015 design DSL embedded in OCaml. The library can be used for front end **Fast Nativ** design tasks up to the synthesis stage where a VHDL or Verilog netlist is generated. Libraries for fast Writing hardware in OCaml, simulation using LLVM, waveform Multiarchit **Running OCaml in hardware** viewing and co-simulation with Icarus Verilog are provided. Andrew Ray HardCaml-RiscV is a simple Portable By pipelined RV32I core, targetted towards a FPGA implementation and built with HardCaml.

OCaml: Safety Critical

OCaml: Predictable Robots!

Creating safe robots with Imandra

Kostya Kanishev Follow

Fur Statio Ga Col

Ru

Fast

From self-driving cars to medical surgeons, robots have become ubiquitous. Ensuring they operate safely and correctly is evermore important. The most popular middleware for robotics is the open-sourced Robot OS. We have begun work on developing an <u>Imandra</u> interface to Robot OS, opening up the world of robotics to the latest advancements in automated reasoning. In this post, we showcase our early results, discuss our roadmap and our submission for a talk at the upcoming ROSCon 2018 (Madrid, Spain).

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