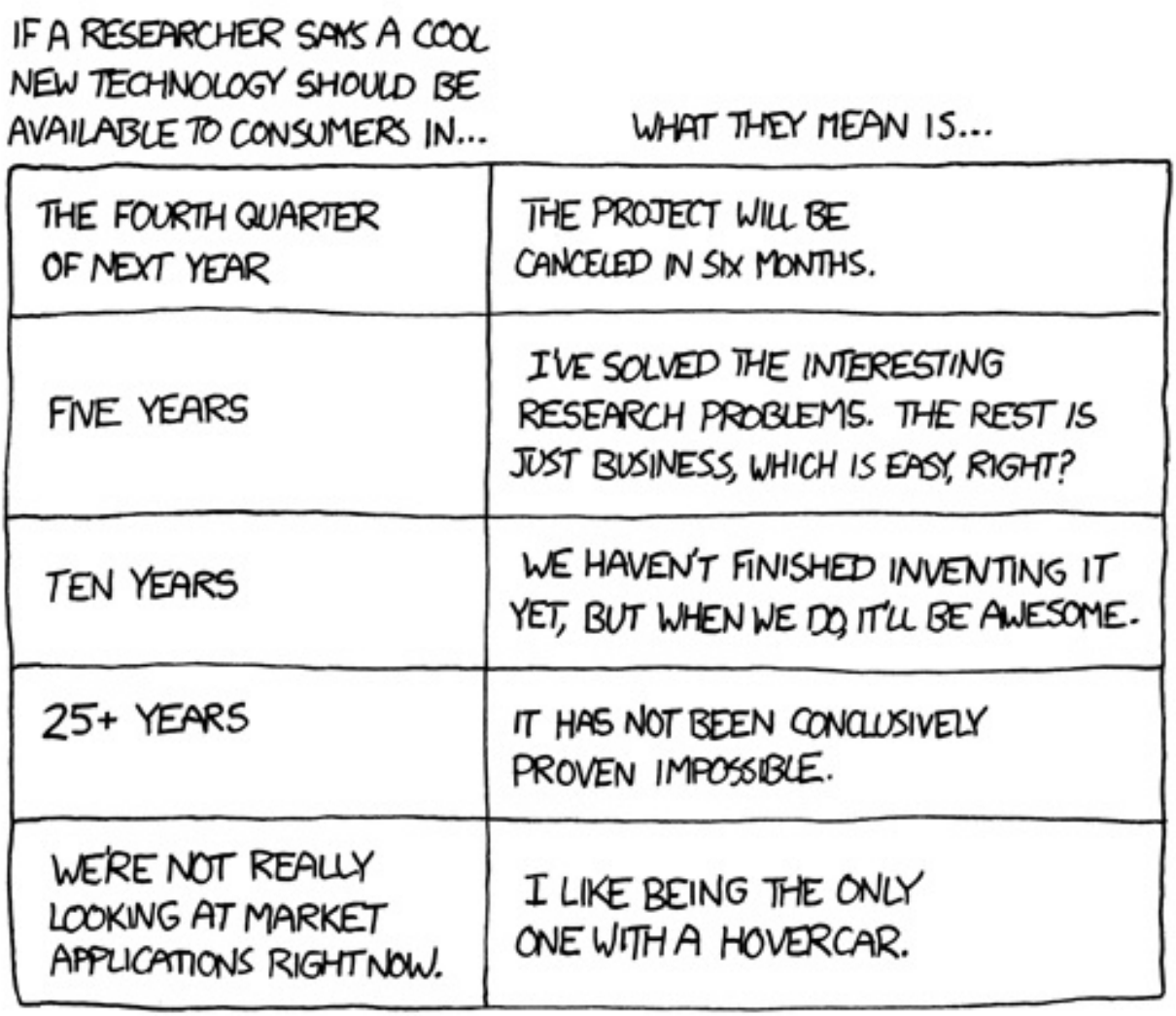
Meeting 23: Objects

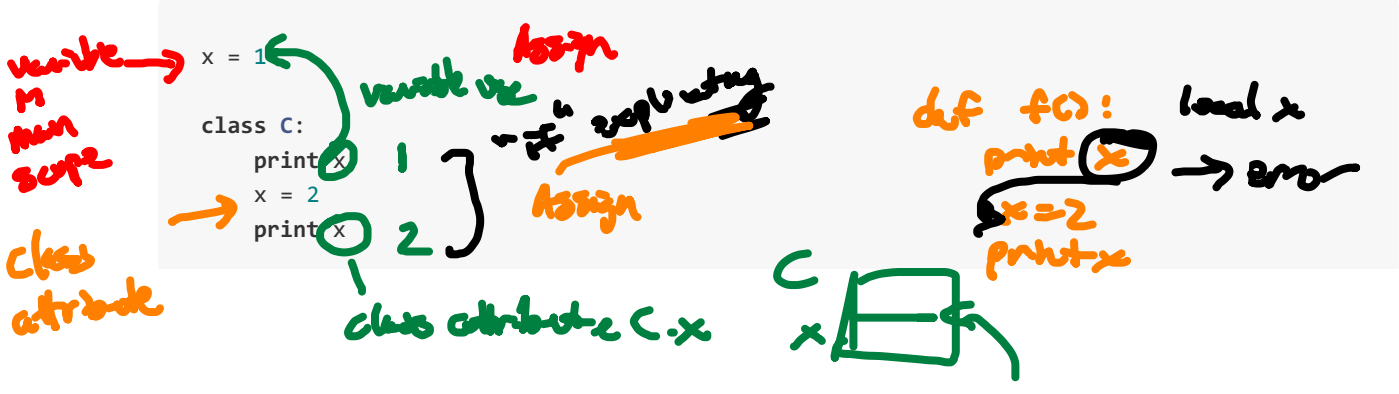


IF A RESEARCHER SAYS A COOL NEW TECHNOLOGY SHOULD BE AVAILABLE TO CONSUMERS IN...	WHAT THEY MEAN IS...
THE FOURTH QUARTER OF NEXT YEAR	THE PROJECT WILL BE CANCELED IN SIX MONTHS.
FIVE YEARS	I'VE SOLVED THE INTERESTING RESEARCH PROBLEMS. THE REST IS JUST BUSINESS, WHICH IS EASY, RIGHT?
TEN YEARS	WE HAVEN'T FINISHED INVENTING IT YET, BUT WHEN WE DO, IT'LL BE AWESOME.
25+ YEARS	IT HAS NOT BEEN CONCLUSIVELY PROVEN IMPOSSIBLE.
WE'RE NOT REALLY LOOKING AT MARKET APPLICATIONS RIGHT NOW.	I LIKE BEING THE ONLY ONE WITH A HOVERCAR.

Announcements

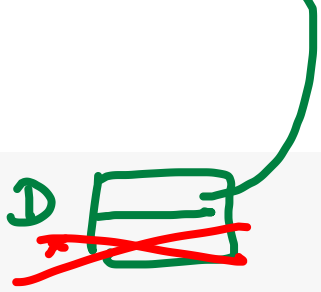
- HW6 due 11/17
- Project status due 11/17 (in your project repo)

Class Scoping Puzzle



```
class D(C):
    print x

print C.x
print D.x
```



```
>>> x = 1
>>>
>>> class C:
...     print x
...     x = 2
...     print x
...
1
2
>>> class D(C):
...     print x
...
1
>>> print C.x
2
>>> print D.x
2
```

class C:

- dynamic scoping

x = 12
class C:
    if False:
        x = 10
print x

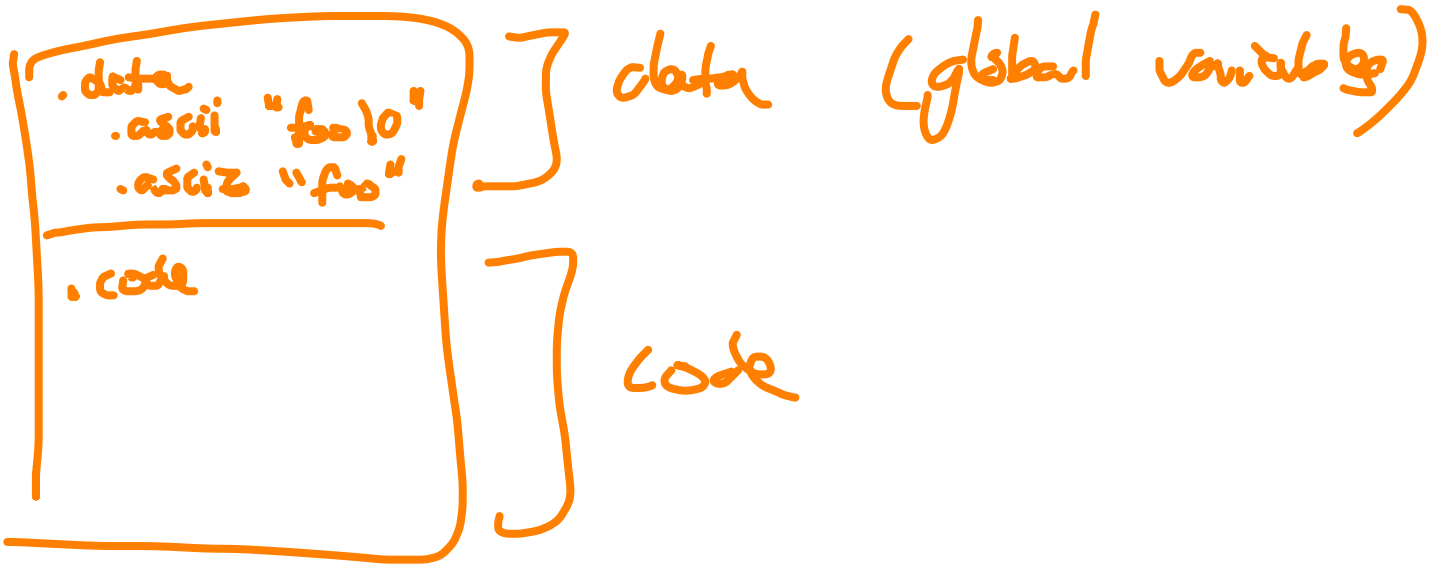
def f():

- static scoping

x = 12
def f():
    if False:
        x = 10
print x — unitialized variable

Questions

1. Compiling classes 79 ✓
2. Conditions & loops ✓
3. Class attributes ✓
4. Strings in assembly ✓



class C:
    ≡
    class B:
        ≡

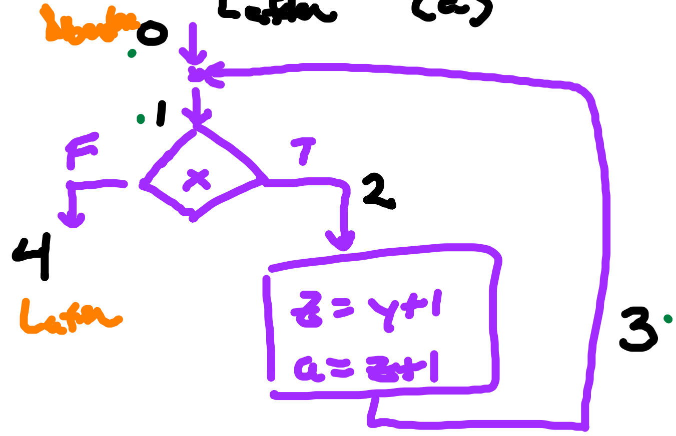
tmpC = create_class(...)

tmpB = create_class(...)

B = tmpB
→ set_attr(tmpC, "B", ...)

L_{before} 0
while[1] x:
  2 z = y + 1
     a = z + 1
  3
L_{after} 4

L_{after} {a}



			1a	1b	1c	2a
L_0	∅	∅	{a,x}	{a,x}	{y,x}	{y,x, a}
L_1	∅	{a,x}	{a,x}	{a,x}	{y,x,a}	{y,x, a}
L_2	∅	∅	∅	{y,x}	{a,y}	{x,y}
L_3	∅	∅	{a,x}	{a,x}	{a,x}	{y, x, a}
L_4	{a}	{a}	{a}	{a}	{a}	{a}

while e:
    s_{body} ← body
object code

def isinstance(n, While):
  L1 = L4 ∪ ... and ... (L_1) = L1
  while fixpoint:
    ⓐ L3 = ... - L1 ..., L0 = ... L1 ...
    ⓑ L2 = liveness(n.body, L3)
    ⓒ L1 = L1 ∪ L2

meta code

L_{before} (0 while, x_{cond} :
2
S_{body}
3
4 , L_{after}) $\overset{\text{def}}{=}$

L_{after}

$L_{\text{before}}(s, L)$

Solve $\overset{\text{def}}{=}$

$L_0 \overset{\text{def}}{=} L_1$

$L_1 \overset{\text{def}}{=} L_2 \cup L_4 \cup \{x_{\text{cond}}\}$

$L_2 \overset{\text{def}}{=} L_{\text{before}}(S_{\text{body}}, L_3)$

$L_3 \overset{\text{def}}{=} L_1$

$L_4 \overset{\text{def}}{=} L_{\text{after}}$

and
return L_0