# **Debugging Domain-Specific Languages**

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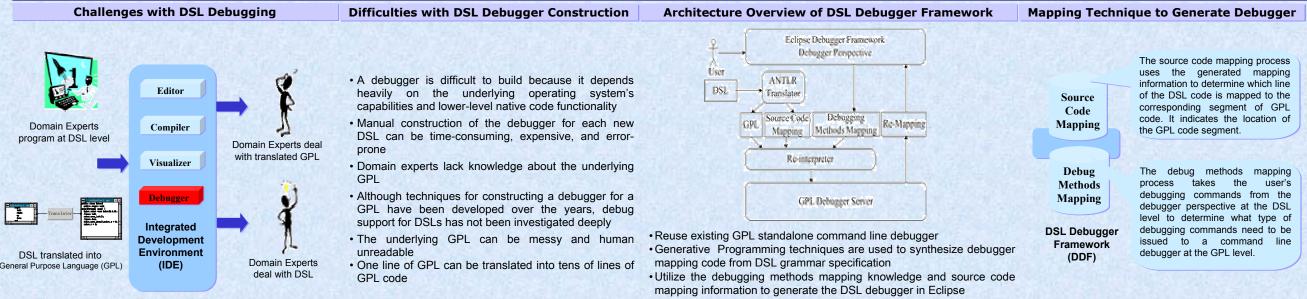
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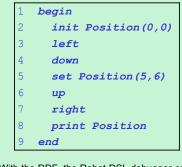
The DSL Debugger Framework (DDF) contributes a mapping technique for augmenting existing DSL grammars to generate the hooks needed to interface with a supporting infrastructure written for Eclipse that assists in debugging a program written in a DSL. This poster presents the challenges of debugging with a DSL, as well as a case study describing two techniques for adding the debugging concern to a grammar.



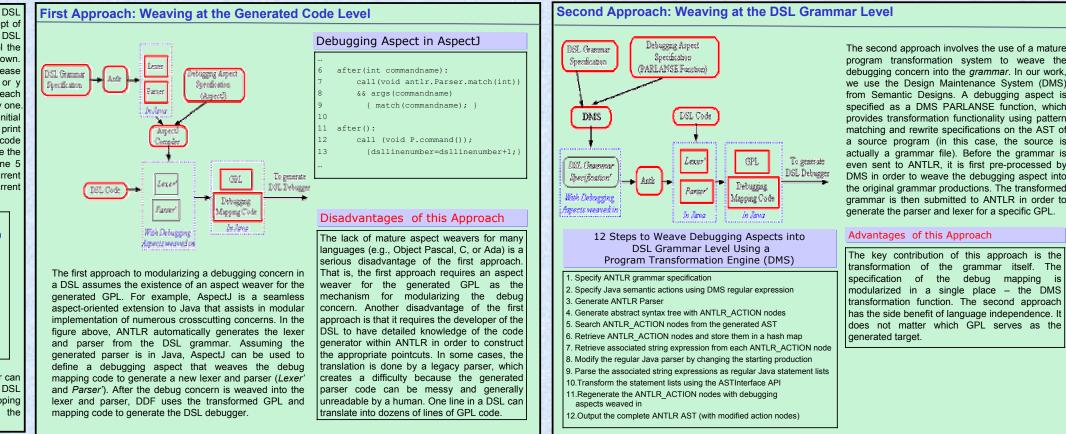
 Map the GPL debugger output messages back to the DSL level through the wrapper interface

### A Case Study with Two Different Approaches

This section presents a very simple DSL that will be used to illustrate the concept of debugging with a DSL. The Robot DSL consists of four commands that control the robot movement: up, down, right and down. Every command will increase or decrease the position of the robot along the x or coordinates. As a side effect. each command will also increase the timer by one Additional Robot DSL statements are: initial statement set statement, and print statement. Following is the sample code written in the Robot DSL - line 2 initialize the robot's beginning position as (0, 0); line 5 forces (5, 6) as the robot's new current position; line 8 prints the robot's current position



Nith the DDF, the Robot DSL debugger can be generated automatically from the DSL grammar provided that an explicit mapping specified between the DSL and the ranslated GPI



The source code mapping process uses the generated mapping information to determine which line of the DSL code is mapped to the corresponding segment of GPL code. It indicates the location of

The debug methods mapping user's debugging commands from the debugger perspective at the DSL level to determine what type of debugging commands need to be issued to a command line

Debugging: A Crosscutting Grammar Concern				
-				
command				
: ( RIGH	r			
(	dsllinenumber=dsllinenumber+1;			
	fileio.print("	//move right");		
	fileio.print("	x=x+1;");		
	gplbeginline=fileio.getLinenumber()	1		
	fileio.print("	<pre>time=time+1;");</pre>		
	gplendline=fileio.getLinenumber();			
	fileio.print(" ");			
	filemap.print(" mapping.add(new M	p("+dsllinenumber+", \"Robot.java\","+gplbeginline+"	<pre>,"+gplendline+"));");</pre>	
}				
LEFT				
{	dsllinenumber=dsllinenumber+1;			
	fileio.print("	<pre>//move left");</pre>		
	fileio.print("	x=x-1;");		
	gplbeginline=fileio.getLinenumber(			
	fileio.print("	<pre>time=time+1;");</pre>		
	<pre>gplendline=fileio.getLinenumber();</pre>			
	fileio.print(" ");			
	filemap.print(" mapping.add(new M	p("+dsllinenumber+", \"Robot.java\","+gplbeginline+"	<pre>,"+gplendline+"));");</pre>	
,				
1 UP	and the second s			
(	dsllinenumber=dsllinenumber+1;			
	fileio.print("	//move up");		
	fileio.print("	y=y+1;");		
	gplbeginline=fileio.getLinenumber(			
	fileio.print(" gplendline=fileio.getLinenumber();	<pre>time=time+1;");</pre>		
	<pre>gplendline=filelo.getLinenumber(); fileio.print(" ");</pre>			
		p("+dsllinenumber+", \"Robot.java\","+gplbeginline+"		
	riiemap.print(- mapping.add(new M	p("dsillenumber+", ("Robot.java\","+gpibeginline+"	,-+gpiendline+"));");	
1				

To define this mapping, additional semantic actions inside each grammar production are defined. These mapping aspects crosscut the entire DSL grammar specification. Manually specifying these aspects can be expensive and error-prone, which compromises the advantages of using a DSL.

#### **DSL Debugger Perspective in Eclipse**

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To Debug 23	🗝 🖬 😡= Variables 🔀 Breakpoints 👘 🎘 🍬 👯 👻
▶ 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Position(x,y) = Position(5, 7)
main (\)()2sdk1.4.0_03\bin\)java.exe	())= Details
	Position( 5, 7)
Robot.rob 🔀	
<pre>init Position(0,0) left  down set Position(5,6) up  right print Position end</pre>	
	2
Construction of the second sec	■ ☜    / ∠   ☎ ▣ -
Console 🔀 Tasks Console (Debugging Robot DSL)	

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