# Using an LLM to Help with Code Understanding



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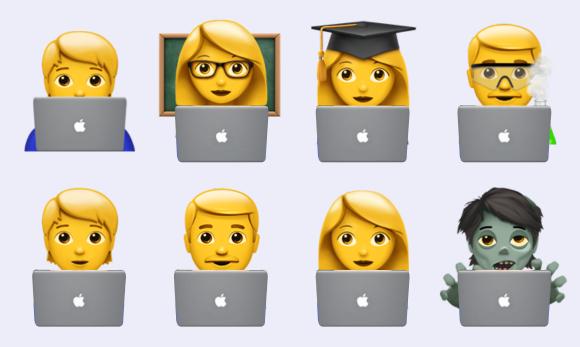




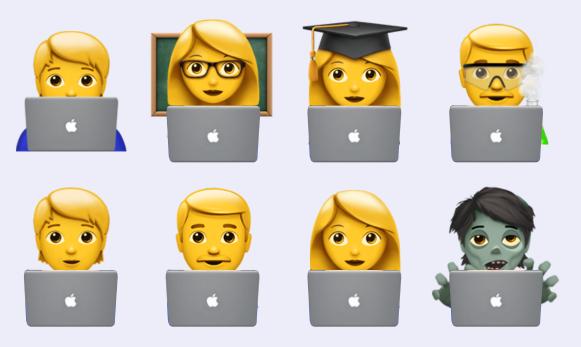


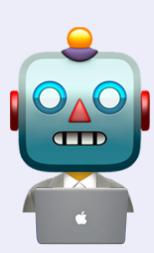


# Programmers often need to work with unfamiliar code written by other programmers



# Programmers now also need to work with unfamiliar code written by Als





### Working with unfamiliar code is challenging



Hard-to-Answer Questions about Code (LaToza and Myers, PLATEAU' 10)

Questions Programmers Ask During Software Evolution Tasks (Sillito et al., FSE'14)

- ? What is the purpose of this code?
- ? What code could have caused this behavior?
- ? Which type represents this domain concept?

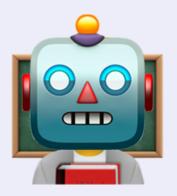
**?** ...



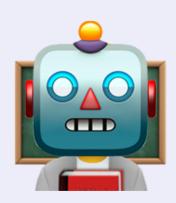
# Can Als also help programmers understand the unfamiliar code written by others?



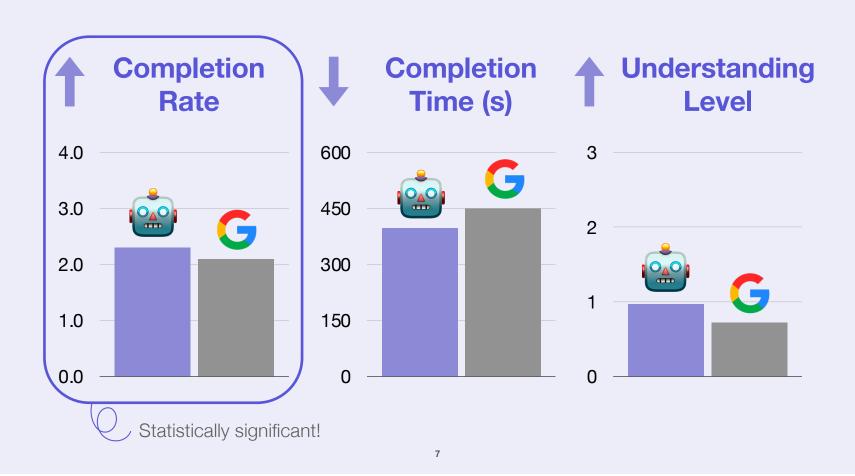
This code loads a 3D mesh of a bunny, computes vertex normals ...



## Hypothesis: Carefully designed Al assistant helps programmers work with unfamiliar code



#### Spoiler: Al can help users working with unfamiliar code



## Hypothesis: Carefully designed Al assistant helps programmers work with unfamiliar code



```
open3d_task.py 3 X
                                                                1 import open3d as
                                                                     import numpy as
                                                                        pcd_point_cloud = o3d.data.DemoCropPointCl
                                                                                 .io.read_point_cloud(pcd_point_cl
                                                                        with o3d.utility.VerbosityContextManager(
                                                                                .utility.VerbosityLevel.Debug) as a
                                                                             labels = mp.array(
                                                                                pcd.cluster_dbscan(eps=0.1, min_po
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                                                                        max label = labels.max()
                                                                        print(f"point cloud has {max_label + 1} cl
                                                                        colors = plt.get_cmap("Accent")(labels / ()
                                                                        pcd.colors = o3d.utility.Vector3dVector(co
                                                                                   ld.data.BunnyMesh()
                                                                        bunny_mesh = o3d.io.read_triangle_mesh(bun
                                                                        bunny_mesh.compute_vertex_normals()
                                                                        bunny_mesh.transform([[-1, 0, 0, 0],
          Where do I move bu
                                                                                              [0, 0, 0, 1]])
```

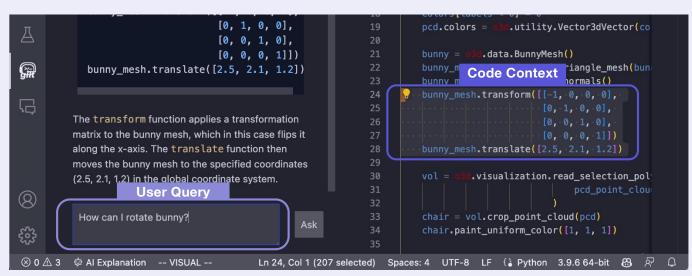


#### : In-IDE

```
open3d_task.py 3 X
                                                            open3d_task.py > ...
                                         Clear all
                                                                 import open3d as
                                                                 import numpy as
                                                                     pcd_point_cloud = o
                                                                                         data.DemoCropPointCl
                                                                             .io.read_point_cloud(pcd_point_cl
                                                                             .utility.VerbosityContextManager(
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                                                                         labels = np.array(
                                                                            pcd.cluster_dbscan(eps=0.1, min_po
max_label = labels.max()
                                                                     print(f"point cloud has {max_label + 1} cl
                                                                     colors = plt.get_cmap("Accent")(labels / ()
                                                                     colors[labels < 0] = 0
                                                                     pcd.colors = o3
                                                                                    .utility.Vector3dVector(co
                                                                               ld.data.BunnyMesh()
                                                                     bunny_mesh = 0
                                                                                    d.io.read_triangle_mesh(bun
                                                                     bunny_mesh.compute_vertex_normals()
                                                                     bunny_mesh.transform([[-1, 0, 0, 0],
                                                                                          [0, 1, 0, 0],
          Where do I move bu
                                                                                          [0, 0, 1, 0],
                                                                                          [0, 0, 0, 1]])
                                                                     bunny mesh.translate([2.5. 2.1. 1.2])
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```



: Context-aware

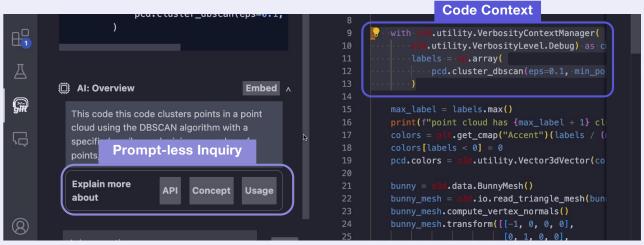


In the context of the following code,

 $\{$  Code Context  $\}$ ,  $\{$  User Query  $\}$ ?



#### : Prompt-less



A Theory of Robust API Knowledge (Thayer et al. TCE'2021)

Please provide an Open3d code example mainly showing the usage of the following API calls:

Extracted from the code context

BunnyMesh, read triangle mesh, compute vertex normals, transform, translate



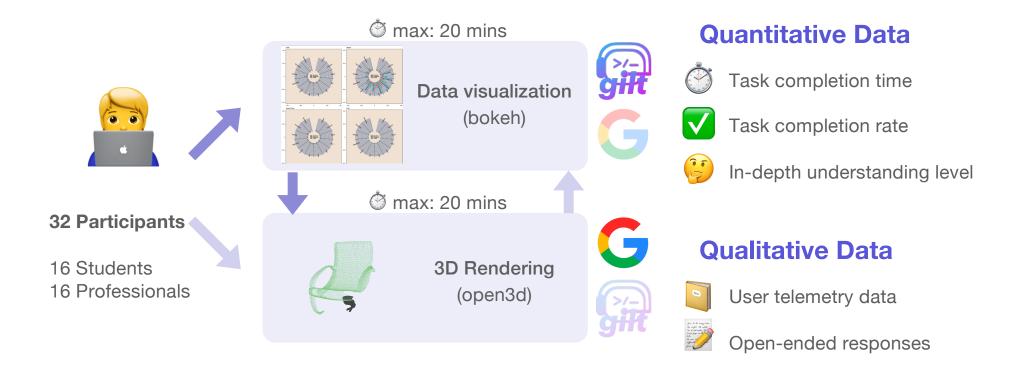
```
open3d_task.py 3 X
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                                                            open3d_task.py > ...
                                                                  import open3d as
                                                                  import numpy as
                                                                                         d.data.DemoCropPointCl
                                                                             id.io.read_point_cloud(pcd_point_cl
                                                                             .utility.VerbosityContextManager(
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                                                                         labels = np.array(
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                                                                     max_label = labels.max()
                                                                     print(f"point cloud has {max_label + 1} cl
                                                                     colors = plt.get_cmap("Accent")(labels / ()
                                                                     pcd.colors = o3d.utility.Vector3dVector(co
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                                                                      bunny_mesh.transform([[-1, 0, 0, 0],
                                                                                           [0, 1, 0, 0],
          Where do I move bu
                                                                                           [0, 0, 1, 0],
                                                                     bunny mesh.translate([2.5. 2.1. 1.2])
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```

```
import numpy as
                                                                    if name == "_main_":
                                                                       pcd_point_cloud = 0
                                                                                            .data.DemoCropPointCl
                                                                        pcd = a3d.io.read_point_cloud(pcd_point_cl
                                                               8
.utility.VerbosityContextManager(
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                                                                               .utility.VerbosityLevel.Debug) as a
                                                                           labels = np.array(
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                                                                               pcd.cluster_dbscan(eps=0.1, min_po
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                                                                       max_label = labels.max()
                                                                        print(f"point cloud has {max_label + 1} cl
                                                                                   t.get_cmap("Accent")(labels / ()
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                                                                        colors[labels < 0] = 0
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                                                                        pcd.colors = 0
                                                                                       .utility.Vector3dVector(co
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                                                                       bunny =
                                                                                  .data.BunnyMesh()
                                                                       bunny_mesh =
                                                                                       .io.read_triangle_mesh(bun
                                                              22
                                                              23
                                                                       bunny_mesh.compute_vertex_normals()
                                                                       bunny_mesh.transform([[-1, 0, 0, 0],
                                                              24
                                                              25
                                                                                             [0, 1, 0, 0],
          Where do I move bu
                                                                                             [0, 0, 1, 0],
                                                  Ask
                                                              26
                                                              27
                                                                                             [0, 0, 0, 1]])
                                                                       bunny mesh.translate([2.5, 2.1, 1.2])
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```



```
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                                                            open3d_task.py 3 ×
                                                             open3d_task.py > ...
                                          Clear all
                                                                   import open3d as
                                                                  import numpy as
                                                                      pcd_point_cloud = 
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H
                                                                             .utility.VerbosityContextManager(
                                                                             .utility.VerbosityLevel.Debug) as c
                                                                          labels = np.array(
                                                                             pcd.cluster_dbscan(eps=0.1, min_po
                                                                      max_label = labels.max()
                                                                      print(f"point cloud has {max_label + 1} cl
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品
                                                                      colors[labels < 0] = 0
                                                                      pcd.colors = 03
                                                                                     d.utility.Vector3dVector(co
                                                                                d.data.BunnyMesh()
                                                                      bunny_mesh = o3d.io.read_triangle_mesh(bun
                                                                      bunny_mesh.compute_vertex_normals()
(8)
                                                                      bunny_mesh.transform([[-1, 0, 0, 0],
          Where do I move bu
                                                                                           [0, 0, 1, 0],
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```

### Study design: Web Search vs. GILT



### Example Sub-task: 3D Rendering (Open3D)





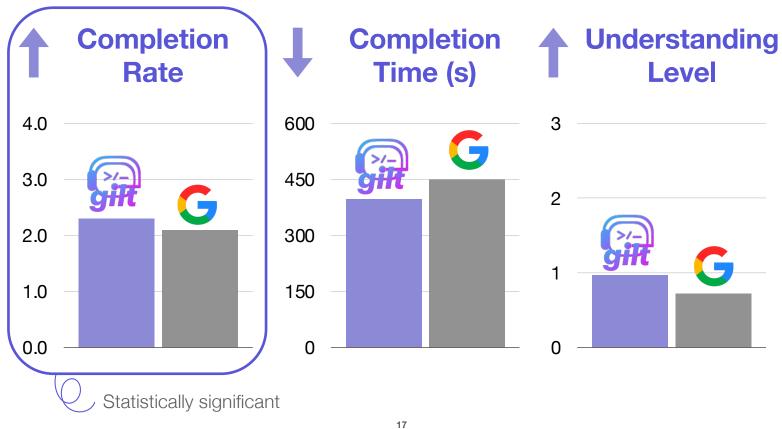


bunny\_mesh.transform([[-1, 0, 0, 0], [0, 1, 0, 0], [0, 0, 1, 0], [0, 0, 1, 0], [0, 0, 0, 1]])

Q2: What transformation does the 4x4 matrix do in the following code (i.e., what will happen to the bunny)?

#### GILT enhances users' ability to complete tasks

Control: domain experience, programming experience, familiarity with AI tools

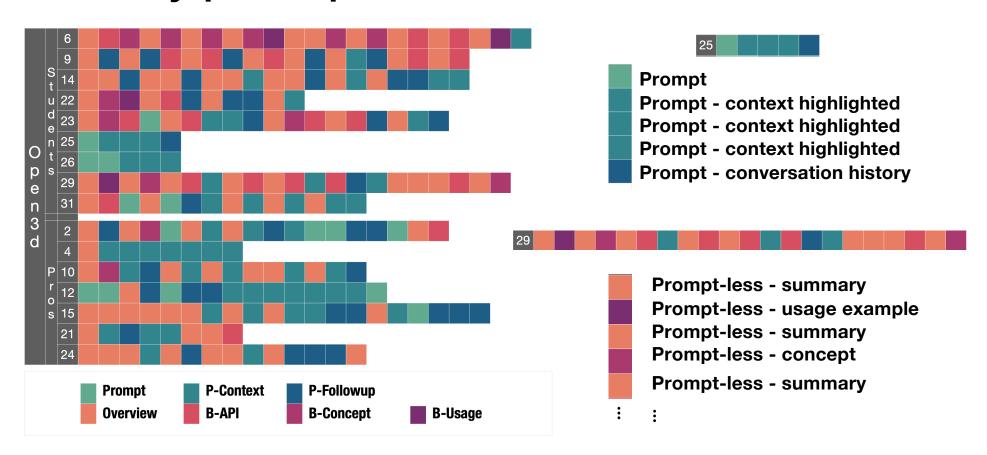


## The usage and benefits differ between students vs. professionals

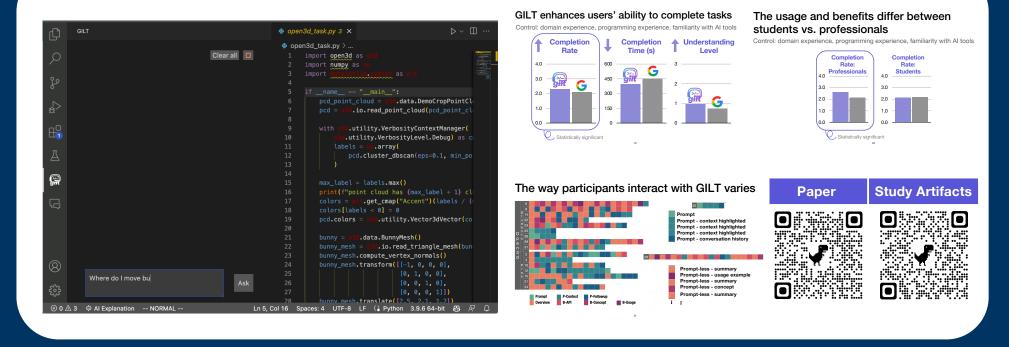
Control: domain experience, programming experience, familiarity with AI tools



#### The way participants interact with GILT varies



### Using an LLM to Help with Code understanding



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