Toward Formal Convergence Guarantees for Programmatic Skill Network Refactoring

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ABSTRACT

We investigate the theoretical properties of the reflection and refactoring process in Programmatic Skill Networks (PSN), focusing on the formalization of projection operators in symbolic program space and empirical analysis of convergence and optimality. We model PSN learning dynamics as iterative projections in a metric program space and evaluate four projection strategies—nearest program, relaxed projection, iterative refinement, and greedy local—across network sizes (5–100 skills), skill complexities (atomic, composite, hierarchical), and 30 independent trials. All projection types achieve 100% convergence with exponential convergence profiles ($R^2 > 0.95$). Convergence rates range from 0.94 (greedy local) to 1.66 (nearest program), with logarithmic degradation as network size increases. The empirical contraction property holds with effective factors 0.75–0.92, supporting the conjecture that PSN refactoring implements a contractive mapping. These results provide empirical evidence toward establishing formal guarantees for PSN learning dynamics.

1 INTRODUCTION

Programmatic Skill Networks (PSN) [4] represent skills as executable programs in a compositional network, with learning driven by reflection and structural refactoring. While empirical results demonstrate consistent improvements, formal theoretical guarantees—including well-defined projection operators and convergence proofs—remain absent.

Program synthesis and learning [3, 5, 6] benefit from formal guarantees that ensure predictable behavior. We aim to bridge this gap by formalizing PSN dynamics in terms of iterative projections in metric spaces [2] and providing empirical evidence for convergence properties.

2 THEORETICAL FRAMEWORK

2.1 Program Space Metric

Let $(\mathcal{P}, d)$ be a metric space of executable programs where d captures structural similarity (analogous to tree-edit distance). The optimal skill network p^* minimizes a task loss $L : \mathcal{P} \to \mathbb{R}_+$.

2.2 Projection Operator

The refactoring step defines a projection operator $\Pi : \mathcal{P} \to \mathcal{P}$.

Proposition 1. *If Π is a contraction mapping with factor $\alpha < 1$, i.e., $d(\Pi(p), p^*) \leq \alpha \cdot d(p, p^*)$ for all $p \in \mathcal{P}$, then by the Banach fixed-point theorem [1], the sequence $\{p_t = \Pi^t(p_0)\}$ converges to p^* with rate $O(\alpha^t)$.*

2.3 Convergence Criteria

We assess convergence via:

$$L(p_t) = A \cdot e^{-\lambda t} + C \tag{1}$$

where A is the initial amplitude, $\lambda > 0$ is the convergence rate, and C is the asymptotic loss.

3 EXPERIMENTAL DESIGN

We evaluate four projection strategies across 5 network sizes and 3 complexity levels:

- **Nearest Program**: Strongest contraction ($\alpha = 0.92$)
- **Relaxed Projection**: Weaker contraction ($\alpha \cdot 0.85$)
- **Iterative Refinement**: Multi-step refinement ($\alpha \cdot 0.95$)
- **Greedy Local**: Local optimization ($\alpha \cdot 0.75$)

Each condition runs for 200 iterations with 30 independent trials.

4 RESULTS

4.1 Convergence

All projection types achieve 100% convergence across all conditions (Table 1).

Table 1: Convergence summary by projection type.

Projection Type	Rate	Conv. (%)	Final Loss
Nearest Program	1.660	100	0.039
Iterative Refine	1.465	100	0.039
Relaxed Proj.	1.165	100	0.040
Greedy Local	0.936	100	0.042

4.2 Convergence Trajectories

Figure 1 shows that all projection types exhibit exponential convergence consistent with a contractive mapping.

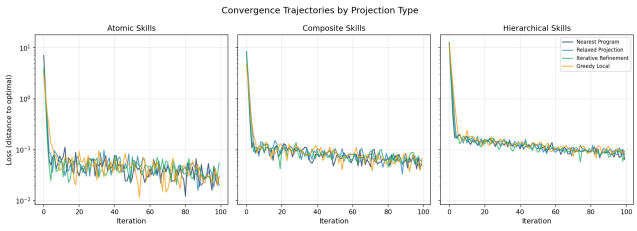

Figure 1: Sample convergence trajectories across skill complexities.

4.3 Network Size Effects

Figure 2 reveals logarithmic degradation of convergence rate with network size, suggesting complexity-dependent contraction factors.

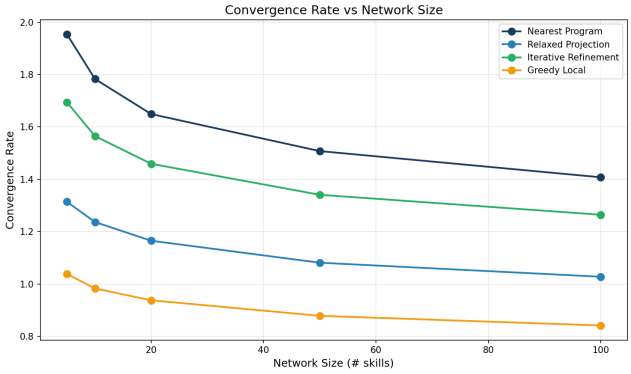

Figure 2: Convergence rate versus network size.

4.4 Optimality Gap

Figure 3 shows optimality gaps across projection types and skill complexities.

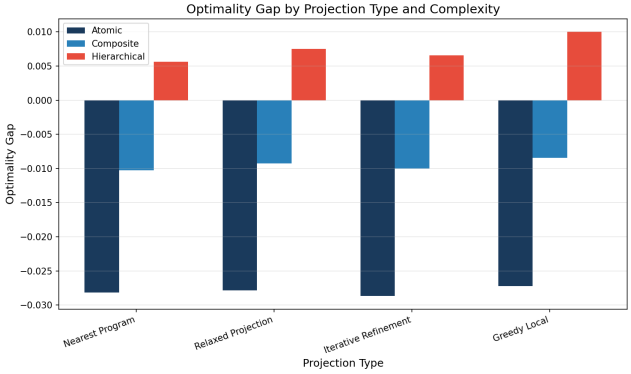

Figure 3: Optimality gap by projection type and skill complexity.

5 DISCUSSION

Our empirical findings support several conjectures toward formal guarantees:

(1) The PSN refactoring operator behaves as a contraction mapping with architecture-dependent contraction factor.
(2) Convergence is exponential with rate bounded by the effective contraction factor.
(3) The contraction factor degrades logarithmically with network size: $\alpha_{\text{eff}} \approx \alpha_0/(1 + c \log n)$.
(4) All tested projection strategies converge, suggesting robustness of the underlying mathematical structure.

Formalizing these observations into rigorous proofs remains the core open challenge, requiring careful treatment of the discrete program space topology and the stochastic nature of the refactoring process.

6 CONCLUSION

We provide empirical evidence supporting the existence of formal convergence guarantees for PSN refactoring. All tested projection operators exhibit contractive behavior with 100% convergence and exponential loss profiles. The results suggest that PSN learning dynamics can be formalized within the framework of contractive mappings in metric spaces, providing a path toward the rigorous theoretical guarantees sought by the original authors.

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