

## A Specialized LLM Chain-of-Thought Framework

Our reward engineering pipeline employs four expert LLMs that work in a structured chain-of-thought workflow: Think LLM ( $\mathcal{M}_{\text{think}}$ ), Code LLM ( $\mathcal{M}_{\text{code}}$ ), Analysis LLM ( $\mathcal{M}_{\text{analysis}}$ ), and Repair LLM ( $\mathcal{M}_{\text{repair}}$ ). This architecture ensures systematic reward function generation by decomposing the complex task into distinct, focused stages with clear role boundaries and information flow constraints.

The chain-of-thought approach prevents common issues in single-model reward generation, such as inconsistent reasoning, code-logic misalignment, and insufficient error handling. Each LLM operates within strict role constraints to maintain workflow integrity.  $\mathcal{M}_{\text{think}}$  focuses purely on conceptual analysis without code implementation,  $\mathcal{M}_{\text{code}}$  translates structured analysis into executable functions,  $\mathcal{M}_{\text{analysis}}$  leverages performance data for systematic improvements, and  $\mathcal{M}_{\text{repair}}$  handles error correction while preserving original design intent.

This modular design enables targeted model selection for each subtask, allowing deployment of reasoning-optimized models for analysis, code-specialized models for implementation, and debugging-focused models for error correction. The structured information flow ensures that each stage builds upon validated outputs from previous stages, creating a robust and interpretable reward generation process.

### A.1 Prompt for Think LLM

$\mathcal{M}_{\text{think}}$  decomposes natural language task descriptions into structured reward design logic, focusing on objective identification, observable analysis, and component boundaries without code generation.

Listing 1: Prompt for  $\mathcal{M}_{\text{think}}$  (Think LLM)

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```
1 You are an expert in reward function design. Your task is to analyze the given
   reinforcement learning task and provide structured reasoning for reward component
   design. DO NOT WRITE ANY CODE.
2 Follow these analysis steps strictly:
3
4 1. **Task & Environment Analysis**
5   - What is the main goal of this task?
6   - What are the key state variables available?
7   - What are the physical and behavioral constraints?
8
9 2. **Objective Identification & Prioritization**
10  - Identify the primary objective (most critical for task success)
11  - List 2-3 secondary objectives that support the main goal
12  - Explain the priority ranking and trade-offs between objectives
13
14 3. **Reward Component Design Logic**
15  - For each objective, specify which observables should be used
16  - Describe the desired behavior for each component (encourage/discourage)
17  - Suggest normalization approaches (e.g., exponential, clipping, scaling)
18  - Consider balance between exploration and exploitation
19
20 4. **Edge Case Analysis**
21  - Identify potential boundary conditions or failure modes
22  - Describe scenarios where the agent might exploit the reward
23  - Suggest safeguards against unintended behaviors
24
25 **Input Context:**
26 Task Description: {TASK_DESC}
27 Environment Code: {ENV_CODE}
28 Available Observables: {OBSERVABLES}
29
30 **Output Format:**
31 Provide detailed reasoning for each section above. Focus on the logic and rationale
   behind each design decision. This analysis will be used by a code implementation
   specialist to create the actual reward function.
```

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## A.2 Prompt for Code LLM

$\mathcal{M}_{\text{code}}$  translates structured analysis into executable reward functions, ensuring code validity and environment compatibility.

Listing 2: Prompt for  $\mathcal{M}_{\text{code}}$  (Code LLM)

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```
1 You are a reward function implementation specialist. Based on the provided analysis,
   implement a working compute_reward function. Output ONLY the Python code wrapped in
   ```python ``` blocks.
2
3 **Implementation Requirements:**
4 1. Function signature: def compute_reward(self, pos, action, state, terminated):
5 2. Return: (total_reward: float, components: Dict[str, float])
6 3. Initialize custom attributes: if not hasattr(self, 'attr'): self.attr = init_value
7 4. Define constants at function start using uppercase names
8 5. Add null checks for inputs to prevent runtime errors
9 6. Normalize components using np.exp, np.tanh, or np.clip
10 7. Keep individual component values in reasonable ranges [-5, 5]
11
12 **Input Analysis from M_think:**
13 {ANALYSIS_CONTENT}
14
15 **Environment Interface:**
16 - pos: Agent position (e.g., pos[0] = x-coordinate)
17 - action: Action vector taken by the agent
18 - state: Full observation vector from environment
19 - terminated: Boolean indicating episode termination
20
21 **Code Constraints:**
22 - Use only provided variables (pos, action, state, terminated) and valid self attributes
23 - Implement each reward component identified in the analysis
24 - Apply appropriate normalization for each component
25 - Ensure the function handles edge cases gracefully
26
27 Output only the complete compute_reward function implementation.
```

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## A.3 Prompt for Analysis LLM

$\mathcal{M}_{\text{analysis}}$  improves reward functions using training performance data, identifying ineffective components and unintended behaviors.

Listing 3: Prompt for  $\mathcal{M}_{\text{analysis}}$  (Analysis LLM)

---

```
1 You are a performance analysis specialist for reward function optimization. Your task is
   to enhance the existing reward function based on training results.
2
3 Structure your response in two parts:
4
5 **Part 1: Performance Analysis**
6 Analyze the training metrics and identify:
7 - Key performance trends (convergence, plateau, instability patterns)
8 - Ineffective reward components (low correlation with success metrics)
9 - Unintended agent behaviors (actions that game the reward system)
10 - Specific improvement opportunities based on the data
11
12 **Part 2: Improved Implementation**
13 Provide an updated compute_reward function that addresses the identified issues:
14 - Preserve effective components that correlate with task success
15 - Modify or remove problematic components
16 - Add new components only if clearly justified by performance gaps
17 - Maintain code structure and return format
```

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```

18
19 **Input Performance Data:**
20 Training Metrics: {TRAINING_METRICS}
21 Agent Behavior Observations: {BEHAVIOR_NOTES}
22 Current Reward Function: {CURRENT_CODE}
23
24 **Optimization Guidelines:**
25 - Focus on fitness_score as the primary optimization target
26 - Balance component magnitudes to prevent any single component from dominating
27 - Address training instability through better normalization
28 - Ensure changes align with the original task objectives
29
30 Provide both the analysis reasoning and the improved code implementation.

```

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## A.4 Prompt for Repair LLM

$\mathcal{M}_{\text{repair}}$  fixes runtime errors in generated code while preserving the original reward logic and component structure.

Listing 4: Prompt for  $\mathcal{M}_{\text{repair}}$  (Repair LLM)

```

1 You are a code debugging specialist for reward functions. Fix the runtime error in the
  provided code without changing the reward logic or adding new features.
2
3 **Error Information:**
4 Error Type: {ERROR_TYPE}
5 Error Message: {ERROR_MSG}
6 Error Context: {ERROR_CONTEXT}
7
8 **Faulty Code:**
9 {FAULTY_CODE}
10
11 **Fix Requirements:**
12 1. Preserve all original reward components and their intended behavior
13 2. Fix only the specific error causing the runtime failure
14 3. Maintain the function signature and return format
15 4. Use only variables available in the environment interface
16 5. Keep all constants and normalization approaches unchanged
17 6. Ensure the fixed code handles similar errors in the future
18
19 **Available Environment Variables:**
20 - pos: Position tuple (pos[0] = x, pos[1] = y)
21 - action: Action array from the agent
22 - state: Full state observation vector
23 - terminated: Episode termination flag
24 - self.* attributes: Only those defined in the environment class
25
26 **Common Fix Patterns:**
27 - Replace undefined variables with correct state indices
28 - Add missing hasattr checks for custom attributes
29 - Fix array indexing errors with proper bounds checking
30 - Correct mathematical operations that cause overflow/underflow
31
32 Output only the corrected compute_reward function wrapped in ```python ``` blocks.

```

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## B Dual Dynamic Optimization Mechanisms

This section presents the two adaptive mechanisms that enhance reward function generation through dynamic parameter adjustment and model selection strategies. The LLM selector (LLMSelector class) and temperature

adjustment (EntropyDynamicTemperature class) constitute the dual dynamic adjustment mechanism, each implementing distinct optimization logic to achieve adaptive responses to task requirements and performance feedback.

## B.1 Performance-Based Model Selection

The LLM selector dynamically allocates models for each role according to cumulative performance, task-specific requirements, and exploration needs. Specialized model pools are maintained for distinct stages, and multiple strategies are available to balance optimization and diversity.

### B.1.1 Stage-Specific Model Pools

Different task stages employ dedicated pools of candidate models, though certain models may appear in multiple pools due to overlapping capabilities (e.g., DeepSeek-Coder for both reasoning and debugging). Table 1 summarizes the mapping.

Table 1: Stage-specific model pools for dynamic selection

Stage	Candidate Models
Environment Understanding	DeepSeek-R1, DeepSeek-Coder
Reward Design	Qwen2.5-Coder, CodeGemma
Performance Analysis	Gemma-3, Llama-3.1
Error Debugging	DeepSeek-Coder, Qwen2.5

### B.1.2 Multi-Strategy Selection Logic

The system implements three complementary selection strategies:

- **Round-robin:** Ensures fair usage by cycling through models within the stage pool.
- **Stage-based:** Combines 40% random exploration with 60% preference-based selection from curated lists.
- **Performance-oriented (default):** Dynamically evaluates and scores models based on effectiveness and reliability.

Algorithm 1 outlines the decision process, where exploration probability adapts to usage history and enforced switching prevents over-dependence on a single model.

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**Algorithm 1** Dynamic Model Selection Algorithm

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```
1: Input: Current stage  $s$ , iteration  $i$ , reward history  $H$ , strategy  $\sigma$ 
2: Output: Selected model  $m$ 
3: if  $\sigma = \text{round\_robin}$  then
4:    $m \leftarrow \text{models}[s][i \bmod |\text{models}[s]|]$ 
5: else if  $\sigma = \text{stage\_based}$  then
6:   if  $\text{random}() < 0.4$  then
7:      $m \leftarrow \text{random\_choice}(\text{models}[s])$ 
8:   else
9:      $m \leftarrow \text{preferred\_models}[s][i \bmod |\text{preferred\_models}[s]|]$ 
10:  end if
11: else ▷ Performance-oriented
12:   for each model  $m_j$  in  $\text{models}[s]$  do
13:     Calculate reward-based performance and stability
14:     Assign fused score to  $\text{scores}[m_j]$ 
15:   end for
16:    $m \leftarrow \text{argmax}_{m_j} \text{scores}[m_j]$  with exploration adjustment
17: end if
18: return  $m$ 
```

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This procedure integrates both exploitation and exploration. The exploration rate begins at 20% and can rise to 50% with repeated model usage, while enforced switching every two iterations further promotes diversity.

### B.1.3 Performance Evaluation Framework

The performance-oriented strategy relies on a multi-component scoring system that balances peak reward, consistency, stability, and historical robustness. The fused score is expressed compactly as:

$$\text{FinalScore} = (1 - \gamma) \cdot \underbrace{\underbrace{(0.7 \cdot \text{MaxReward} + 0.3 \cdot \text{MeanReward} \times (0.8 + 0.2e^{-\text{StdDev}}))}_{\text{BasePerformance}}}_{\text{CurrentScore}} + \gamma \cdot \text{HistoricalScore}$$

where  $\gamma = 0.5$  balances recent and historical performance. This formulation prioritizes maximum reward (70%) while smoothing results through mean reward (30%). The exponential stability factor penalizes high variance, and historical integration prevents overfitting to short-term fluctuations.

## B.2 Entropy-Driven Temperature Adjustment

As shown in Algorithm 2, temperature adjustment modulates LLM sampling randomness based on reward component diversity, performance trends, and output confidence to balance exploration and exploitation throughout the optimization process.

### B.2.1 Multi-Dimensional Adjustment Criteria

Temperature adjustment operates on three key indicators that capture different aspects of generation quality and optimization progress.

Entropy analysis measures reward distribution diversity through kernel density estimation. When entropy falls below 0.3, indicating concentrated distributions that may lead to agent stagnation, temperature increases

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**Algorithm 2** Dynamic Temperature Adjustment

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```
1: Input: Current rewards  $R$ , historical rewards  $H$ , current temperature  $T_{prev}$ 
2: Output: Updated temperature  $T_{new}$ 
3: Calculate entropy:  $entropy \leftarrow KDE\_entropy(R)$ 
4: Calculate confidence:  $confidence \leftarrow 1/coefficient\_of\_variation(R)$ 
5:  $temp\_factor \leftarrow 1.0$ 
6: if  $entropy < 0.3$  then
7:    $temp\_factor \leftarrow temp\_factor \times 1.1$ 
8: else if  $entropy > 0.5$  then
9:    $temp\_factor \leftarrow temp\_factor \times 0.9$ 
10: end if
11: if  $confidence > 0.8$  then
12:    $temp\_factor \leftarrow temp\_factor \times 0.95$ 
13: else if  $confidence < 0.4$  then
14:    $temp\_factor \leftarrow temp\_factor \times 1.05$ 
15: end if
16:  $current\_best \leftarrow \max(R)$ 
17:  $historical\_best \leftarrow \max(H)$ 
18: if  $current\_best < 0.8 \times historical\_best$  then
19:    $temp\_factor \leftarrow temp\_factor \times 2.0$ 
20: else if  $current\_best \geq historical\_best$  then
21:    $temp\_factor \leftarrow temp\_factor \times 0.5$ 
22: end if
23:  $T_{target} \leftarrow T_{prev} \times temp\_factor$ 
24:  $T_{new} \leftarrow 0.9 \times T_{prev} + 0.1 \times T_{target}$ 
25:  $T_{new} \leftarrow clip(T_{new}, 0.1, 1.0)$ 
26: return  $T_{new}$ 
```

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► Entropy-based adjustment

► Increase exploration

► Decrease exploration

► Confidence-based adjustment

► High confidence, stabilize

► Low confidence, explore

► Performance change adjustment

► Performance drop, explore more

► Performance improved, exploit

► Momentum smoothing

► Bound temperature

by 5% to promote exploration. Conversely, when entropy exceeds 0.5, suggesting dispersed distributions that may cause training instability, temperature decreases by 5% to enhance consistency.

Confidence measurement evaluates output consistency based on the inverse coefficient of variation. High confidence situations ( $CV^{-1} \geq 0.8$ ) trigger temperature reduction ( $\times 0.95$ ) to stabilize successful patterns. Low confidence scenarios ( $CV^{-1} \leq 0.4$ ) increase temperature ( $\times 1.05$ ) to expand the search space and discover better solutions.

Performance tracking compares current results with historical best achievements, triggering significant exploration when performance declines, and favoring exploitation when performance improves.

### B.2.2 Smoothing and Coordination Mechanisms

Temperature updates employ momentum smoothing to prevent rapid oscillations that could destabilize the generation process. The new temperature combines 90% of the previous temperature with 10% of the target adjustment, ensuring gradual transitions. Temperature values are constrained within  $[0.1, 1.0]$  to avoid extreme sampling behaviors that could compromise generation quality.

The dual dynamic mechanisms coordinate through shared performance metrics and exploration states. Model selection determines which model to use while temperature adjustment controls how the model outputs, creating synergistic adaptive responses. When model selection favors exploration of new models, temperature adjustment may simultaneously increase randomness to enhance discovery. Conversely, when focusing on high-performing models, temperature typically decreases to stabilize outputs and reinforce exploitation of proven strategies.

## C Experimental Configuration Details

This section provides comprehensive implementation specifications for reproducing the experimental setup and ensuring consistent evaluation across different reinforcement learning environments.

### C.1 Environment Setup and Dependencies

The experimental framework supports multiple RL environments through standardized interfaces and carefully configured dependencies. Table 2 summarizes the key environment specifications.

Table 2: Environment Configuration Specifications

Environment	Action Space	Observation Space
BipedalWalker-v3	Continuous (4D)	24D (joints, velocities, LiDAR)
CartPole-v1	Discrete (2D)	4D (cart pos/vel, pole angle/vel)
Ant-v5	Continuous (8D)	111D (joint pos/vel, torso state, contacts)
SpaceMining-custom	Continuous+Discrete (3D)	53D (agent state, asteroids, mothership)

BipedalWalker-v3 utilizes `gymnasium[box2d]` v0.29.1 with continuous 4-dimensional joint torque control and 24-dimensional observations including joint angles, velocities, and LiDAR sensor data. Episodes terminate after 1600 steps or when the agent falls, with rewards ranging from -100 to over 300 based on forward progress and stability maintenance.

CartPole-v1 employs `gymnasium[classic_control]` v1.3.0 featuring discrete 2-action control (left/right force) and 4-dimensional observations capturing cart position, velocity, pole angle, and angular velocity. Episodes terminate after 500 steps, when the pole angle exceeds 12 degrees, or when the cart position exceeds  $\pm 2.4$  units. The reward corresponds to the duration of pole balancing, with a maximum of 500.

Ant-v5 is implemented with `gymnasium[mujoco]` v5.3.0, featuring an 8-dimensional continuous action space controlling joint torques. Observations include a 111-dimensional state vector encompassing joint

positions/velocities, torso orientation, and contact sensor readings. Episodes terminate if the torso falls or becomes unstable. The reward function combines forward velocity, survival bonus, and control cost, typically ranging from 0 to 6000.

SpaceMining-v1 is a custom-designed environment adhering to the `gymnasium` interface. The observation space is 53-dimensional, integrating agent state (position, velocity, energy, inventory), asteroid features (up to 15 visible asteroids with relative positions and resource amounts), and mothership position. The action space consists of two continuous thrust controls and a binary mining action. Episodes terminate after 2000 steps or on collision. The reward function provides positive feedback proportional to mined resources and penalties for collisions and energy depletion.

Evaluation consistency is maintained through deterministic seeding strategies. Training employs randomized seeds per iteration for robustness, while evaluation uses fixed seeds [5, 10, 15, 20, 25] across all experiments. The software stack requires Python 3.8+, PyTorch 1.12+, and CUDA 11.6+ for GPU acceleration, with CUDA-compatible hardware featuring at least 8GB VRAM recommended for optimal performance.

## C.2 Training Pipeline Configuration

The reinforcement learning training pipeline employs Proximal Policy Optimization (PPO) from Stable-Baselines3 v2.0.0 as the base algorithm. Table 3 details the standardized hyperparameters used across all environments.

Table 3: PPO Training Configuration Parameters

Parameter	Value
Policy Architecture	MlpPolicy [64, 64]
Learning Rate	3e-4 (linear decay)
Batch Size	64 samples
Discount Factor ( $\gamma$ )	0.999
GAE Lambda ( $\lambda$ )	0.95
PPO Clip Range	0.2
Optimization Epochs	10 per update
Value Function Loss	MSE (coef: 0.5)
Entropy Coefficient	0.01
Training Duration	1M timesteps/iteration
Evaluation Frequency	Every 10K timesteps
Evaluation Episodes	10 per checkpoint

The policy architecture uses multilayer perceptron networks with two hidden layers of 64 units each. Learning rate starts at 3e-4 with linear decay scheduling throughout training. Each policy update processes batches of 64 samples with 10 optimization epochs, using a discount factor of 0.999 for long-term reward consideration and GAE lambda of 0.95 for advantage estimation.

Training progresses for 1,000,000 timesteps per iteration with evaluation checkpoints every 1,000 timesteps. Each evaluation uses 10 episodes to assess performance stability. Early stopping triggers when performance plateaus for 5 consecutive evaluations without improvement.

Resource management includes NVML-based GPU utilization monitoring with dynamic device selection based on memory availability and computational load. Memory management features automatic batch size adjustment according to available VRAM. The framework supports multi-environment parallel training with shared policy updates and distributed computing through Ray framework integration for multi-node scaling.

Data storage employs compressed trajectory formats for efficient analysis and replay capabilities. TensorBoard logging captures comprehensive training metrics, reward component tracking, and agent behavior statistics. Model checkpoints save at peak performance points and iteration boundaries, enabling detailed analysis of learning progression and reward function effectiveness throughout the optimization process.



### C.3 Baseline Implementation Fidelity and Budget Alignment

To address concerns regarding the fairness and fidelity of baseline comparisons, we explicitly clarify the implementation details of the primary LLM-based baseline, **Eureka**. Our goal is to ensure methodological fairness rather than feature-level parity.

All reward generation experiments were conducted under a unified local inference infrastructure using the Ollama framework, which guarantees identical model weights and eliminates variability introduced by external APIs. Both Eureka and DyCoT-RE employ the same LLM backbone throughout all experiments.

Crucially, the core evolutionary mechanism of Eureka, as described in the original work, is fully preserved. This includes its population-based mutation strategy, selection based on episodic return, and iterative refinement process. The adaptation to a Gymnasium-style pipeline only affects the interface between reward evaluation and environment execution, and does not modify Eureka’s prompt structure, mutation operators, population dynamics, or evolutionary depth.

While the internal generation procedures of Eureka and DyCoT-RE differ by design, all methods are constrained to *comparable generation budgets per environment*. Differences in population structure or refinement strategy reflect method-intrinsic design choices rather than unequal computational allocation. Importantly, Eureka is not augmented with entropy regulation, temperature scheduling, or model-switching mechanisms beyond those specified in its original formulation.

Under these controlled conditions, any observed performance differences can be attributed to methodological distinctions in reward generation and adaptation, rather than to disparities in model capacity, inference cost, or experimental privilege.

Table 4: Generative Configuration Summary for Eureka and DyCoT-RE (Method-Specific, Budget-Aligned, Backbone-Consistent). All compared methods are evaluated under the same set of local LLM backbones; differences reflect intrinsic methodological designs rather than unequal computational allocation.

Configuration Item	Eureka	DyCoT-RE (Ours)
Local LLM Backbones	codegemma (7B), qwen2.5 (7B), deepseek-r1 (8B), gemma3 (4B), llama3.1 (8B)	
Inference Engine	Ollama (Local)	Ollama (Local)
Reward Generation Paradigm	Evolutionary Mutation	Structured CoT Refinement
Temperature Strategy	Fixed (Original Setting)	Adaptive (Method-Intrinsic)
Control Signals	Episodic Return	Entropy + Confidence + Fitness
Generation Budget	Budget-Aligned	Budget-Aligned

To isolate methodological effects, Eureka and DyCoT-RE are evaluated under an identical set of local LLM backbones with comparable parameter scales. No backbone-specific tuning is introduced for either method.

## D Signal Separation and Entropy Diagnostics

To further investigate the internal characteristics of the DyCoT-RE optimization process, we conduct a signal separation analysis based on normalized entropy statistics and variance decomposition across iterations. This analysis aims to distinguish *intra-iteration stochastic noise* from *inter-iteration structural signal* introduced by the dynamic reasoning and feedback mechanism.

Specifically, we compute the normalized Shannon entropy of reward-related distributions under two settings: (i) a baseline entropy  $H_{\text{noise}}$ , measured within individual iterations to characterize inherent sampling noise, and (ii) a total entropy  $H_{\text{total}}$ , measured across the DyCoT training trajectory, which incorporates both stochastic variation and cross-iteration structural effects. All entropy values are normalized to the range  $[0, 1]$  for comparability across environments.

As shown in Table 5, all environments exhibit relatively high baseline entropy, reflecting the intrinsically uncertain and high-variance nature of LLM-generated reward candidates. This behavior is expected and

consistent with prior observations in language-model-guided reinforcement learning settings.

Table 5: Signal Separation Analysis (excerpt from Appendix D).  $H_{\text{noise}}$ : Baseline entropy (intra-iteration noise).  $H_{\text{total}}$ : Total entropy during DyCoT training. **Ratio  $R$** : Signal-to-noise ratio ( $\sigma_{\text{inter}}^2/\sigma_{\text{intra}}^2$ ).

Environment	$H_{\text{noise}}$ (Baseline)	$H_{\text{total}}$ (DyCoT)	Ratio $R$ (Signal/Noise)
CartPole-v1	$0.905 \pm 0.017$	$0.916 \pm 0.016$	0.83×
BipedalWalker-v3	$0.988 \pm 0.002$	$0.976 \pm 0.011$	<b>95.62×</b>
Ant-v5	$0.894 \pm 0.023$	$0.901 \pm 0.033$	<b>3.60×</b>
SpaceMining	$0.943 \pm 0.008$	$0.944 \pm 0.017$	2.31×

Importantly, absolute entropy values alone are not indicative of optimization effectiveness. Instead, we examine the ratio

$$R = \sigma_{\text{inter}}^2 / \sigma_{\text{intra}}^2,$$

which quantifies the relative strength of inter-iteration structured signal against intra-iteration noise. A higher ratio indicates that the optimization dynamics are dominated by consistent cross-iteration guidance rather than random sampling fluctuations.

The results reveal a pronounced separation effect in complex, high-dimensional environments. In particular, BipedalWalker-v3 demonstrates a signal-to-noise ratio exceeding 95×, suggesting that DyCoT-RE introduces strong and stable inter-iteration structure despite operating under a high-entropy background. Ant-v5 and SpaceMining also exhibit clear signal amplification, though at a more moderate scale.

In contrast, CartPole-v1 shows a ratio below unity, indicating that DyCoT-RE does not significantly enhance structural signal in this low-dimensional and already well-conditioned environment. This outcome aligns with expectations and highlights the task-dependent applicability of the proposed mechanism.

Overall, this diagnostic analysis supports the claim that DyCoT-RE primarily improves optimization by amplifying inter-iteration structure under high-noise conditions, rather than by reducing stochastic entropy directly.