Predictive Compression Dynamics: A Methodological Framework for Computable Information-Driven Modeling

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Dated: October 21, 2025

Abstract

We present *Predictive Compression Dynamics* (PCD), a methodological recipe for constructing *computable*, local functionals $\widehat{\Phi}$ and driving dynamics by gradient flow $\dot{x} = -\nabla\widehat{\Phi}(x)$ with preregistered parameters. Two concrete instances are given: (i) a fixed-graph pair functional and (ii) a smooth compact-support kernel; both yield an attractive inverse-square two-body form (after calibration) and admit Lyapunov descent. We emphasize that these models serve as methodological demonstrations of computable, information-motivated dynamics, without asserting new physical law. We make the MDL split $L_{\mathrm{tot}} = L(M) + L(D \mid M)$ explicit, give a minimal coding scheme linking $-\widehat{\Phi}$ descent to achievable ΔL_{tot}, address well-posedness (smooth-kernel variant), recommend robust integrators (BAOAB for Langevin), and provide a preregistration/model-card template and falsifiers for a chosen model instance. The goal is a reproducible toolbox for compression-driven dynamics across domains.

1 Positioning and Commitments

What this paper is. A disciplined workflow to construct and test *computable* local functionals $\widehat{\Phi}$ whose gradients define dynamics, with explicit preregistration (domain, discretization, kernels, parameters) and sanity checks.

What this paper is not. It does not propose new physical laws; any similarity of pair terms to known potentials is used solely for controlled validation.

2 Operational Domain and Notation

We consider N point agents with positions $x_i \in \mathbb{R}^3$ and positive weights m_i. Computations use finite precision: lattice spacing a_{grid} and b bits/axis, stated *a priori*. A global calibration constant $G_{\mathrm{eff}} > 0$ maps dimensionless forces to physical units. *Design choice:* we use the same m_i in the interaction and as inertial mass; this incidentally yields accelerations independent of m_i by construction.

3 Model–Data Decomposition and Coding Link

Following MDL, we split description length as

$$L_{\mathrm{tot}} = L(M) + L(D \mid M), \tag{3.1}$$

where $L(M)$ encodes modeled regularities and $L(D \mid M)$ encodes residuals given M. A decrease $\Delta L_{\mathrm{tot}} < 0$ corresponds to realized compression. PCD treats a computable, local $\widehat{\Phi}$ as a proxy for (the negative of) an achievable ΔL_{tot}; thus $\dot{x} = -\nabla\widehat{\Phi}$ implements a descent in achievable codelength under the chosen surrogate.

Minimal explicit coding scheme. Let (i,j) range over a symmetric set of "near" pairs. A two-part code describes (i) a shared pairwise template per distance bin and (ii) residual offsets:

- Partition distances into bins $\{B_k\}$ with centers r_k; encode the histogram counts with a prefix-free code.
- For each pair (i,j) with $r_{ij} \in B_k$, encode a residual offset relative to a shared template; the expected residual codelength per pair is a decreasing function $\ell(r_{ij})$.

Then, for fixed binning overhead and under mild regularity,

$$L_{\mathrm{tot}} \approx \mathrm{const} + \sum_{(i,j)} \ell(r_{ij}). \tag{3.2}$$

Choosing $\widehat{\Phi} \propto -\sum_{(i,j)} \ell(r_{ij})$ makes $-\nabla\widehat{\Phi}$ a proxy for the gradient of achievable compression. A smooth choice $\ell(r) \approx (r^2 + a^2)^{-1/2}$ yields closed-form forces below.

4 Information-Motivated Functionals

4.1 Fixed-graph functional (corrected notation)

Let $E \subset \{(i,j) : 1 \le i < j \le N\}$ be a symmetric, degree-bounded edge set. Define

$$\widehat{\Phi}_E(x) = -\sum_{(i,j)\in E} \frac{m_i m_j}{\sqrt{\|x_i - x_j\|^2 + a^2}}, \qquad a > 0. \tag{4.1}$$

The minus sign ensures attraction under descent; a regularizes collisions. The force on i is

$$F_i^{(E)}(x) = -\nabla_{x_i}\widehat{\Phi}_E(x) = -\sum_{\substack{j:\\(i,j)\in E}} m_i m_j \frac{(x_i - x_j)}{\left(\|x_i - x_j\|^2 + a^2\right)^{3/2}}. \tag{4.2}$$

Two-body, $a \to 0$, $(i,j) \in E$ gives the attractive inverse-square form:

$$F_i^{(E)} \to -m_i m_j \frac{x_i - x_j}{\|x_i - x_j\|^3}. \tag{4.3}$$

4.2 Smooth-kernel functional (well-posedness)

To avoid neighbor-set discontinuities, choose a compactly supported, C^1 radial kernel $K_\sigma : [0,\infty) \to \mathbb{R}_{\ge 0}$ with support $\subset [0, R\sigma]$. Define

$$\widehat{\Phi}_K(x) = -\sum_{i<j} m_i m_j \, K_\sigma(\|x_i - x_j\|), \tag{4.4}$$

so $F_i^{(K)}(x) = -\nabla_{x_i}\widehat{\Phi}_K(x)$ is continuous and locally Lipschitz off collisions. If $K_\sigma(r) \sim (r^2 + a^2)^{-1/2}$ near $r = 0$, one recovers the regularized two-body form (4.3).

5 Dynamics and Integrators

With $\dot{x} = -\nabla\widehat{\Phi}(x)$,

$$\frac{d}{dt}\widehat{\Phi}(x(t)) = -\|\nabla\widehat{\Phi}(x(t))\|^2 \le 0, \tag{5.1}$$

so $\widehat{\Phi}$ is a Lyapunov function. We preregister all parameters $(a_{\mathrm{grid}}, b, a, \sigma, \Delta t, m_i, \gamma, T, \mathrm{seeds})$.

Deterministic gradient flow. Explicit Euler:

$$x_i^{(t+\Delta t)} = x_i^{(t)} + \Delta t\, F_i(x^{(t)}), \quad F_i \in \{F_i^{(E)}, F_i^{(K)}\}. \tag{5.2}$$

For stability, use adaptive Δt or semi-implicit variants.

Underdamped Langevin (BAOAB recommended).

$$m_i \ddot{x}_i = F_i(x) - \gamma\, \dot{x}_i + \xi_i(t), \quad \langle \xi_i(t)\xi_j(t')\rangle = 2\gamma k_B T\, \delta_{ij}\delta(t-t'). \tag{5.3}$$

We recommend the BAOAB integrator with reported weak/strong orders.

6 Sanity Checks

With $a \to 0$ and a single pair, (4.3) holds (after one calibration G_{eff}). For $r \gg a$,

$$\frac{r}{(r^2+a^2)^{3/2}} = \frac{1}{r^2}\left(1 - \frac{3a^2}{2r^2} + O\left(\frac{a^4}{r^4}\right)\right), \tag{6.1}$$

so

$$\|F_i^{(E)}\| = m_i m_j \frac{r}{(r^2+a^2)^{3/2}} \approx m_i m_j \frac{1}{r^2}\left(1 - \frac{3a^2}{2r^2}\right). \tag{6.2}$$

These expansions serve purely as numerical consistency checks.

7 Well-posedness

For $a > 0$ and bounded degree, $\widehat{\Phi}_E \in C^1(\mathbb{R}^{3N} \setminus \{x_i = x_j\})$ and $F^{(E)}$ is locally Lipschitz off collisions. For C^1 kernels with bounded K'_σ, $F^{(K)}$ is continuous and locally Lipschitz. Existence and uniqueness follow by Picard–Lindelöf on compact intervals. For dynamic kNN, forces are piecewise smooth; employ hysteresis or prefer the smooth kernel.

8 Preregistered Model Card (example)

Domain. $a_{\text{grid}} = 10\,\mu\text{m}$, $b = 16$.
Functional. $\widehat{\Phi}_K$ with Wendland C^2 kernel ($\sigma = 0.5\,\text{mm}$); softening $a = 50\,\mu\text{m}$.
Dynamics. BAOAB underdamped with ($m_i \equiv 1, \gamma = 0.1, T = 300\,\text{K}$), $\Delta t = 1 \times 10^{-3}\,\text{s}$.
Calibration. Single G_{eff} fit in a dilute two-body sandbox at $r \gg a$.
Sanity checks. Verify (4.3) and the far-field expansion; report seeds and residuals.

9 Falsifiers for a chosen instance

Given fixed ($\widehat{\Phi}$, params), declare the instance falsified if:

(F1) Two-body trajectories disagree with the calibrated inverse-square form beyond numerical error.

(F2) Smooth-kernel vs fixed-graph variants differ systematically at small r beyond topology effects.

(F3) The code-length proxy correlates poorly with realized compression in controlled tests (e.g. $-\widehat{\Phi}$ vs measured L_{tot}).

10 Discussion and Scope

PCD supplies a reproducible route from *computable* information-motivated functionals to concrete dynamics. That simple pairwise surrogates coincide with familiar inverse-square interactions is a feature for validation, not a claim of novelty. Future work will broaden $\widehat{\Phi}$ (e.g. learned local codes, graph Laplacians) under the same preregistration discipline.

Acknowledgments

We thank colleagues for discussions on local estimators, kernels, integrators, and N-body numerics. Earlier drafts that explored alternative framings are superseded by this methodological formulation.

References

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