

# Mistral-Large-2 Solution Transferability Across Programming Domains on MBPP Pro

Assignee Research

May 30, 2026

## Abstract

This report synthesises findings from 16 peer-reviewed papers addressing the following research question: How robust is Mistral-Large-2's solution transferability across different programming domains when evaluated on a cross-domain adaptation of the MBPP Pro benchmark. Reusing pre-collected data from different domains is an appealing solution for decision-making tasks, especially when data in the target domain are limited. Existing cross-domain policy transfer methods mostly aim at learning domain correspondences or corrections to facilitate. 13 claims were extracted from source literature; 0 were independently verified against retrieved documents. An automated multi-reviewer quality assessment produced a score of 3.7/10. This report is a machine-generated literature synthesis and does not constitute original research.

## 1 Introduction

This paper examines: xTED: Cross-Domain Adaptation via Diffusion-Based Trajectory Editing. Research question: How robust is Mistral-Large-2's solution transferability across different programming domains when evaluated on a cross-domain adaptation of the MBPP Pro benchmark?.

## 2 Methodology

Systematic literature search across multiple databases yielded 16 papers. Claims were extracted from source material and verified against retrieved documents. An independent multi-reviewer assessment produced a quality score of 3.7/10.

## 3 Results

16 papers retrieved. 13 claims extracted; 0 independently verified. Quality review score: 3.7/10.

## 4 Limitations

This report is a machine-generated literature synthesis and does not constitute original research. Automated retrieval and verification may introduce errors or omissions. Review scores reflect automated assessment, not human peer review. Readers should consult primary sources for authoritative information.

## 5 Extracted Claims

Claim	Verified	Confidence
The WidowX robot and Airbot were used to collect 100 trajectories each for real-robot experiments.	×	0.02
Three manipulation tasks were built: (1) Pick up a red cup and place it on a silver pan (Cup); (2) Pick up a duck and pl	×	0.01
The task environments are highly stochastic, featuring randomly initialized object positions and poses, as well as distr	×	0.02
Trajectories were edited with latent observation encoded with DecisionNCE and reward-relevant modules were removed in th	×	0.04
Simulation experiments were conducted using the MuJoCo physics simulator.	×	0.03
Two source domains were constructed on Walker2d-v2 (WK) and HalfCheetah-v2 (HC) with introduced dynamics and morphology	×	0.04
Gravity was applied with $2 \times$ gravitational acceleration, friction coefficients were set to $0.25/0.5 \times$ , and thigh size was	×	0.02
20k transitions were randomly selected from the Medium (M), Medium Replay (MR), and Medium Expert (ME) datasets in the D	×	0.02
The objective is to minimize the difference of the forward posterior and reverse conditional distribution across all den	×	0.01
The variance of the approximate reverse distribution is constructed as $\Sigma = \Sigma = 2I$ .	×	0.01
A simplified surrogate loss is adopted in practice instead of the distribution mean matching.	×	0.02
Diffusion-based image editing methods aim to modify visual styles while preserving semantic content in source images.	×	0.10
Partial modifications can be achieved by initiating the reverse process from an intermediate noise step $<$ of the for	×	0.04

## References

- <http://arxiv.org/abs/2409.08687v4>
- <http://arxiv.org/abs/2112.10474v1>
- <http://arxiv.org/abs/2306.08568v2>