



“Calibeating”: Beating Forecasters at Their Own Game

Sergiu Hart

April 2026

“Calibeating”: Beating Forecasters at Their Own Game

Sergiu Hart

Center for the Study of Rationality
Dept of Mathematics Dept of Economics
The Hebrew University of Jerusalem

hart@huji.ac.il

<http://www.ma.huji.ac.il/hart>



Joint work with

Dean P. Foster

**University of Pennsylvania &
Amazon Research NY**

Papers

- Sergiu Hart

“Calibration: The Minimax Proof”, 1995
*Matching, Dynamics and Games for the
Allocation of Resources 2025*

www.ma.huji.ac.il/hart/publ.html#calib-minmax

Papers

- Sergiu Hart
“Calibration: The Minimax Proof”, 1995
Matching, Dynamics and Games for the Allocation of Resources 2025
www.ma.huji.ac.il/hart/publ.html#calib-minmax
- Dean P. Foster and Sergiu Hart
“Smooth Calibration, Leaky Forecasts, Finite Recall, and Nash Dynamics”
Games and Economic Behavior 2018
www.ma.huji.ac.il/hart/publ.html#calib-eq

Papers

- Dean P. Foster and Sergiu Hart
“Forecast Hedging and Calibration”
Journal of Political Economy 2021

www.ma.huji.ac.il/hart/publ.html#calib-int

Papers

- Dean P. Foster and Sergiu Hart
“Forecast Hedging and Calibration”
Journal of Political Economy 2021
www.ma.huji.ac.il/hart/publ.html#calib-int
- Dean P. Foster and Sergiu Hart
“ ‘Calibeating’: Beating Forecasters at Their Own Game”
Theoretical Economics 2023
● Addendum 2024; Errata 2026 (arXiv)
www.ma.huji.ac.il/hart/publ.html#calib-beat

Papers

- Dean P. Foster and Sergiu Hart
“Proper Calibrating”
2025

www.ma.huji.ac.il/hart/publ.html#calib-proper

Calibration

Calibration

- Forecaster says: “***The probability of rain tomorrow is p*** ”

Calibration

- Forecaster says: “*The probability of rain tomorrow is p* ”
- Forecaster is **CALIBRATED** if

Calibration

- Forecaster says: “*The probability of rain tomorrow is p* ”
- Forecaster is **CALIBRATED** if
 - for every forecast p :
in the days when the forecast was p , the proportion of rainy days equals p

Calibration

- Forecaster says: “*The probability of rain tomorrow is p* ”
- Forecaster is **CALIBRATED** if
 - for every forecast p :
in the days when the forecast was p , the proportion of rainy days equals p
(or: is close to p in the long run)

Calibration

Calibration

CALIBRATION *can be guaranteed*
(no matter what the weather will be)

Calibration

CALIBRATION *can be guaranteed*
(no matter what the weather will be)

- Foster and Vohra 1994 [publ 1998]

Calibration

CALIBRATION *can be guaranteed*
(no matter what the weather will be)

- Foster and Vohra 1994 [publ 1998]
- Hart 1995: proof by Minimax Theorem

Calibration

CALIBRATION *can be guaranteed*
(no matter what the weather will be)

- Foster and Vohra 1994 [publ 1998]
- Hart 1995: proof by Minimax Theorem
- . . .

Calibration

CALIBRATION *can be guaranteed*
(no matter what the weather will be)

- Foster and Vohra 1994 [publ 1998]
- Hart 1995: proof by Minimax Theorem
- . . .
- Hart and Mas-Colell 1996 [publ 2000]:
procedure by Blackwell's Approachability

Calibration

CALIBRATION *can be guaranteed*
(no matter what the weather will be)

- Foster and Vohra 1994 [publ 1998]
- Hart 1995: proof by Minimax Theorem
- . . .
- Hart and Mas-Colell 1996 [publ 2000]:
procedure by Blackwell's Approachability
- Foster 1999: simple procedure

Calibration

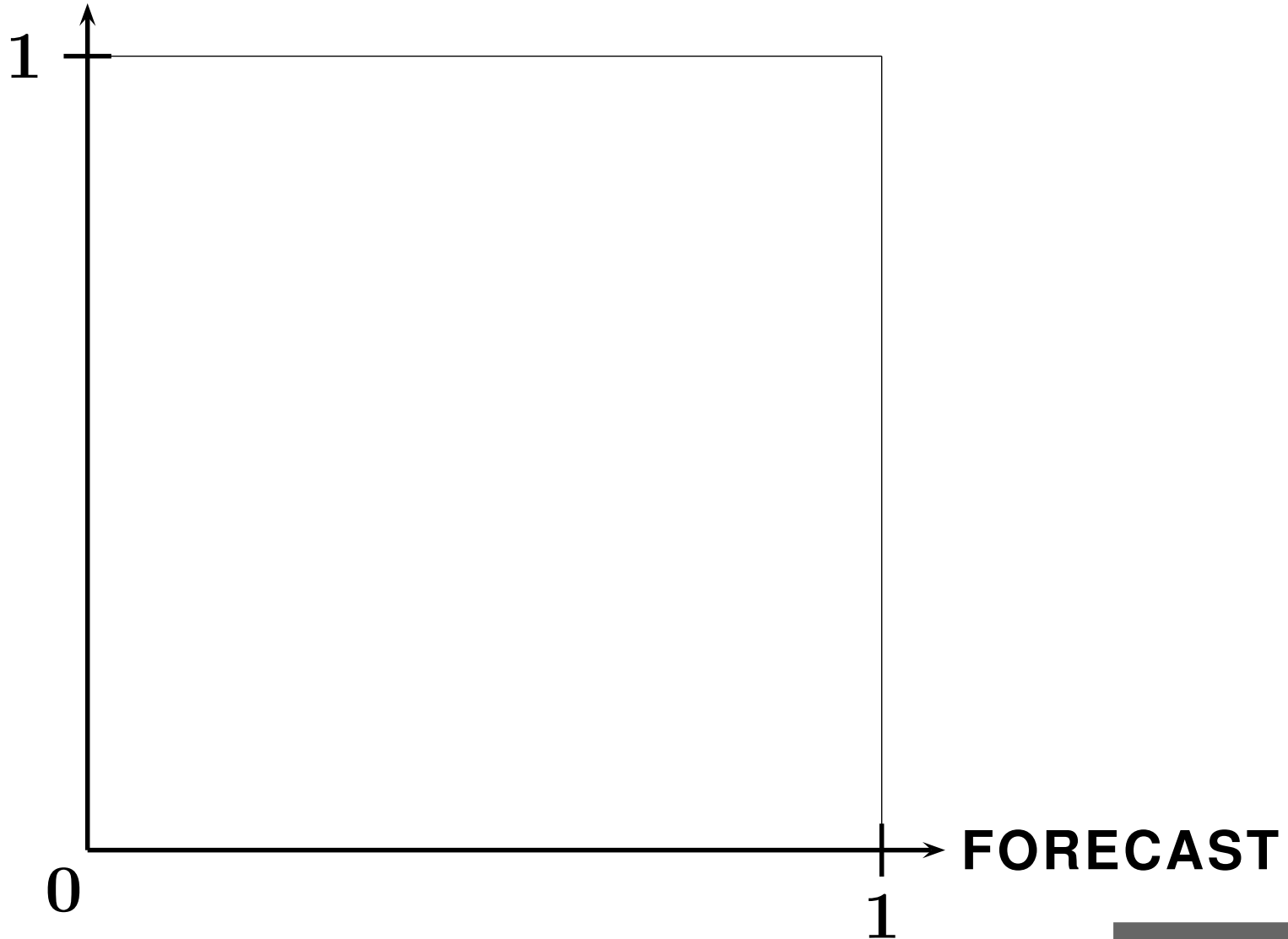
CALIBRATION *can be guaranteed*
(no matter what the weather will be)

- Foster and Vohra 1994 [publ 1998]
- Hart 1995: proof by Minimax Theorem
- . . .
- Hart and Mas-Colell 1996 [publ 2000]:
procedure by Blackwell's Approachability
- Foster 1999: simple procedure
- Foster and Hart 2016 [publ 2021]: simplest
procedure, by "Forecast Hedging"

Forecast-Hedging (FH)

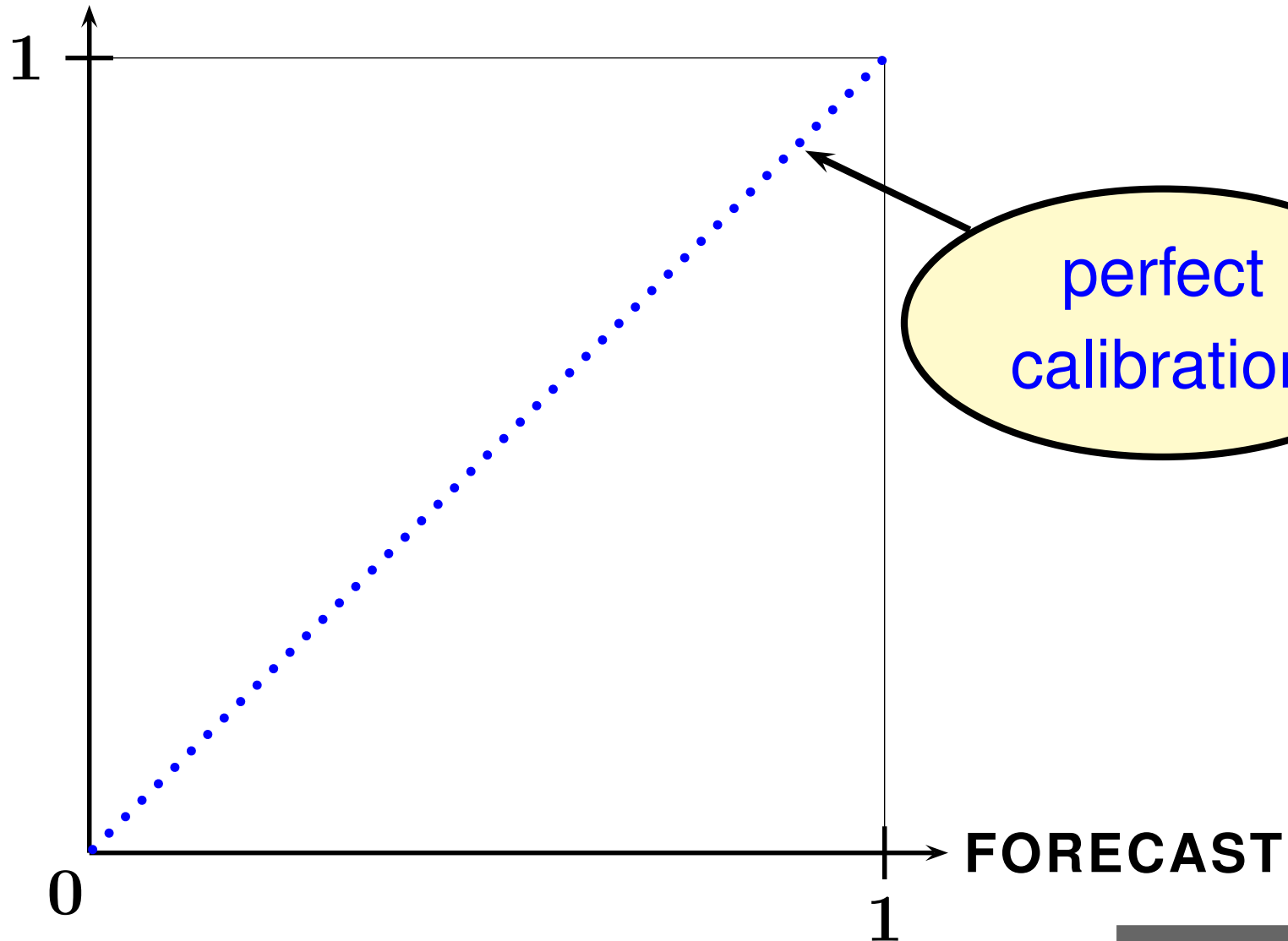
Forecast-Hedging (FH)

AVERAGE ACTION (= frequency of rain)



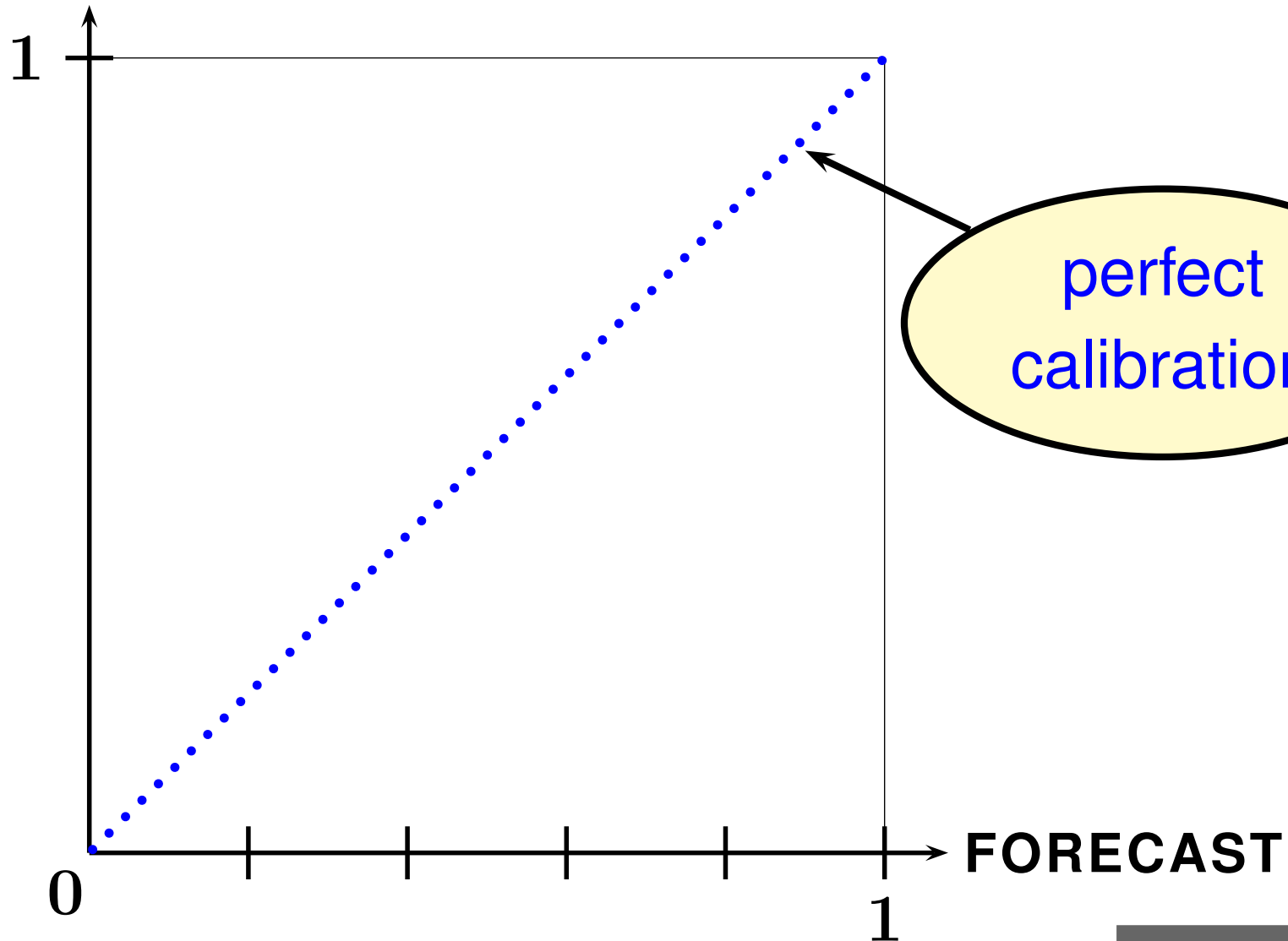
Forecast-Hedging (FH)

AVERAGE ACTION (= frequency of rain)



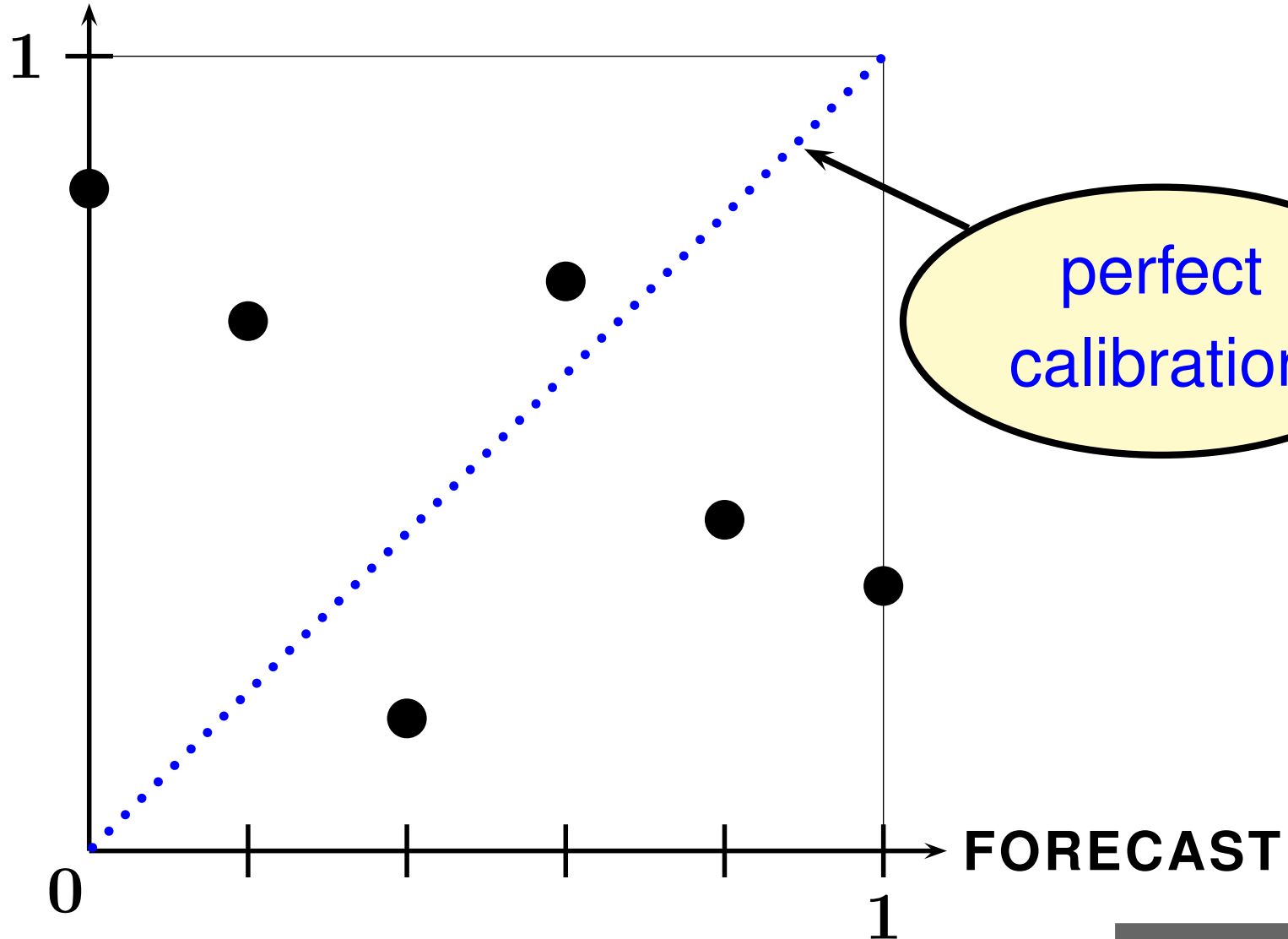
Forecast-Hedging (FH)

AVERAGE ACTION (= frequency of rain)



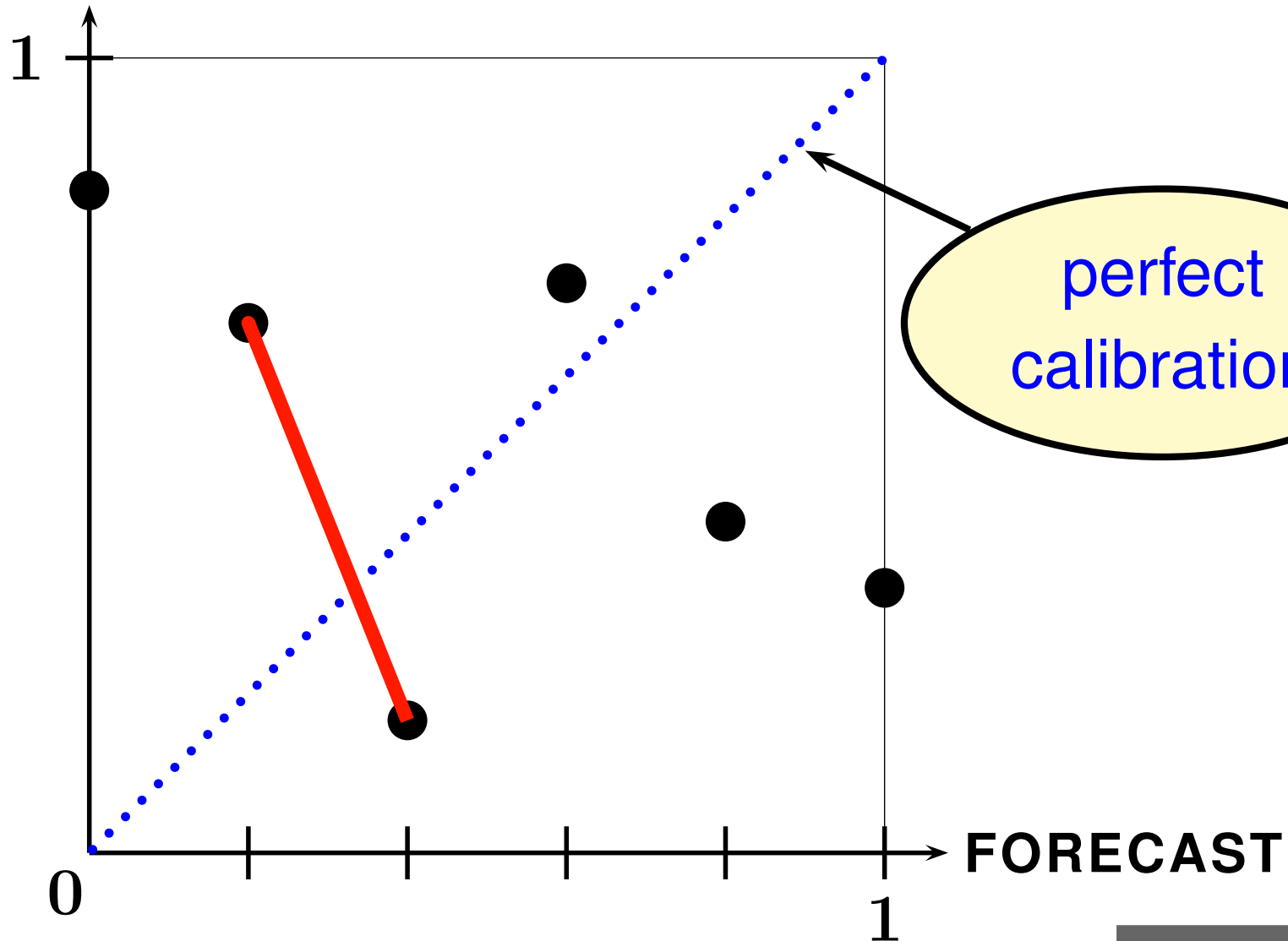
Forecast-Hedging (FH)

AVERAGE ACTION (= frequency of rain)



Forecast-Hedging (FH)

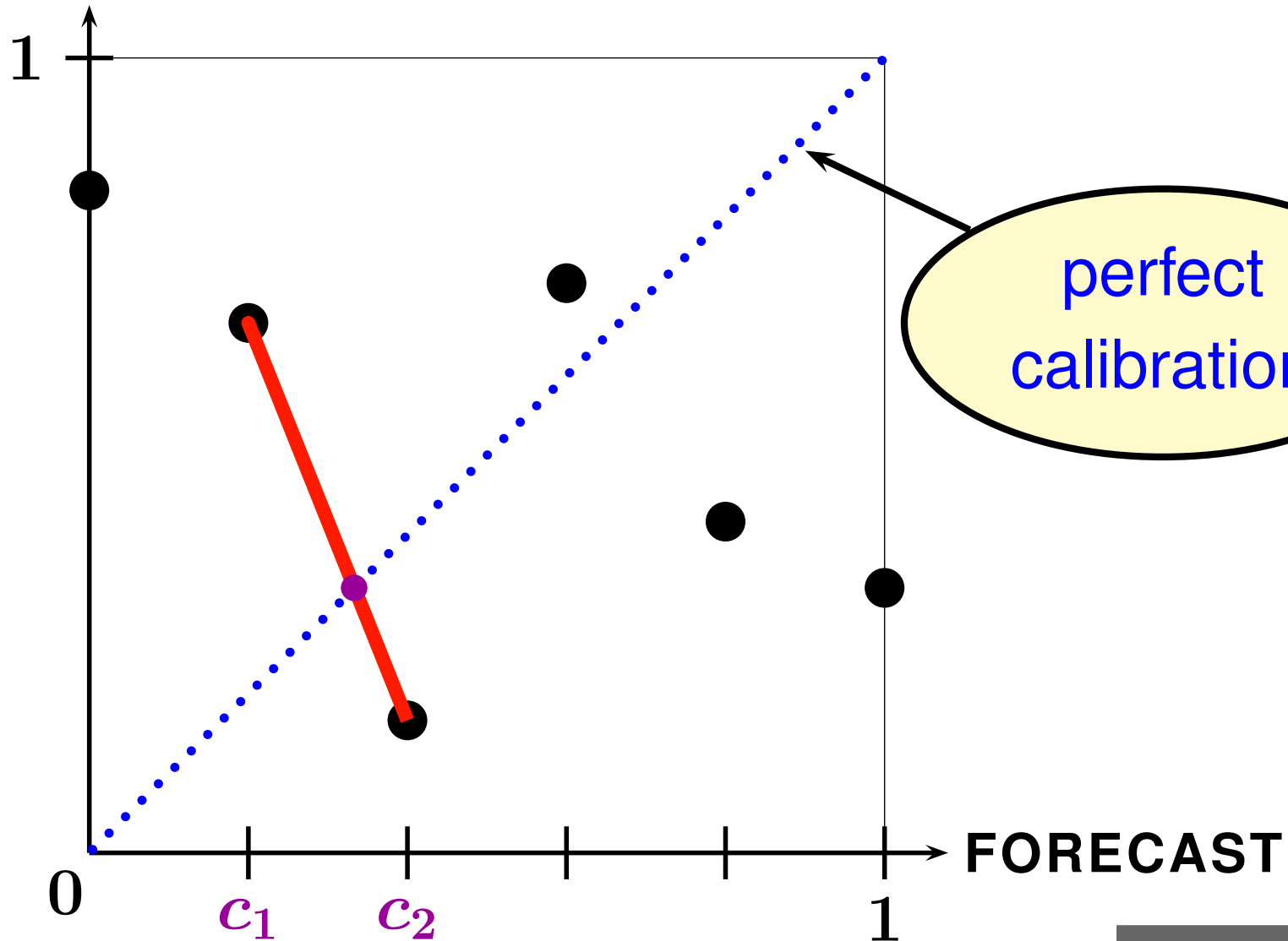
AVERAGE ACTION (= frequency of rain)



perfect calibration

Forecast-Hedging (FH)

AVERAGE ACTION (= frequency of rain)



Forecasting

Forecasting ?

Forecasting ?

BACK-casting !

Forecasting ?

BACK-casting !

(not fore-casting)

Forecasting ?

BACK-casting !

(not fore-casting)

... prophet looking backwards ...

Forecasting ?

BACK-casting !

(not fore-casting)

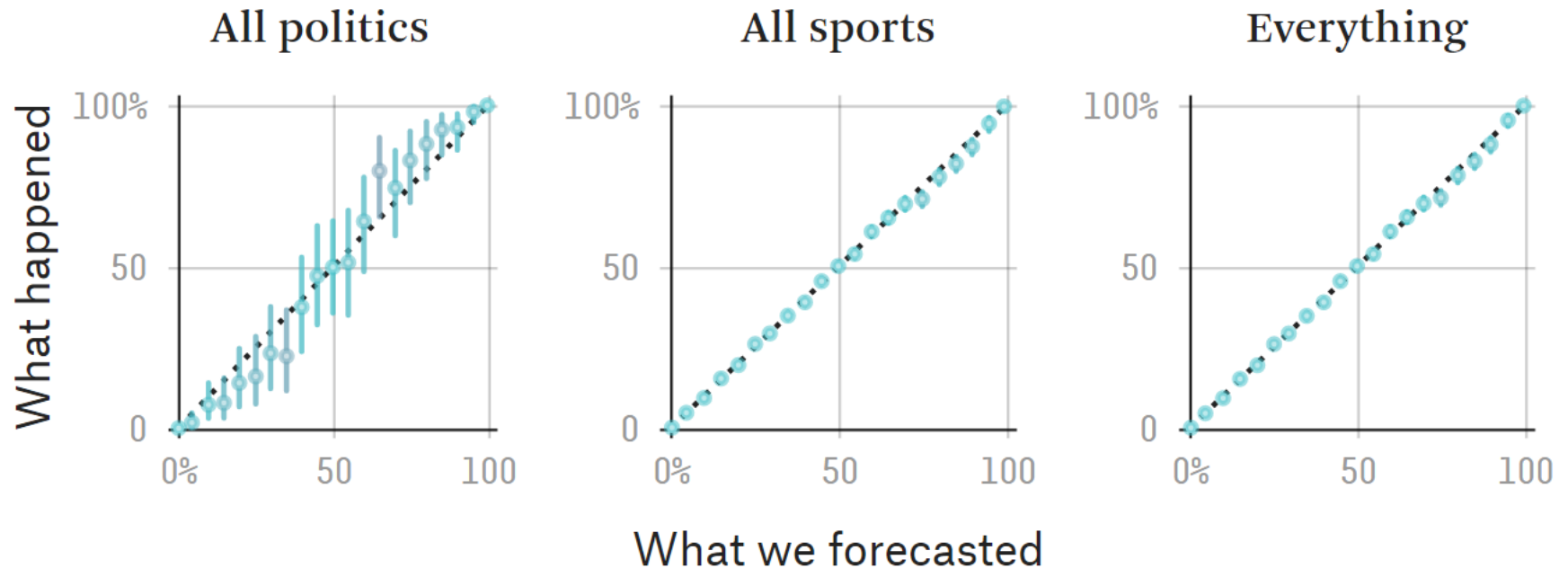
... prophet looking backwards ...

Friedrich von Schlegel (1797)

Walter Benjamin

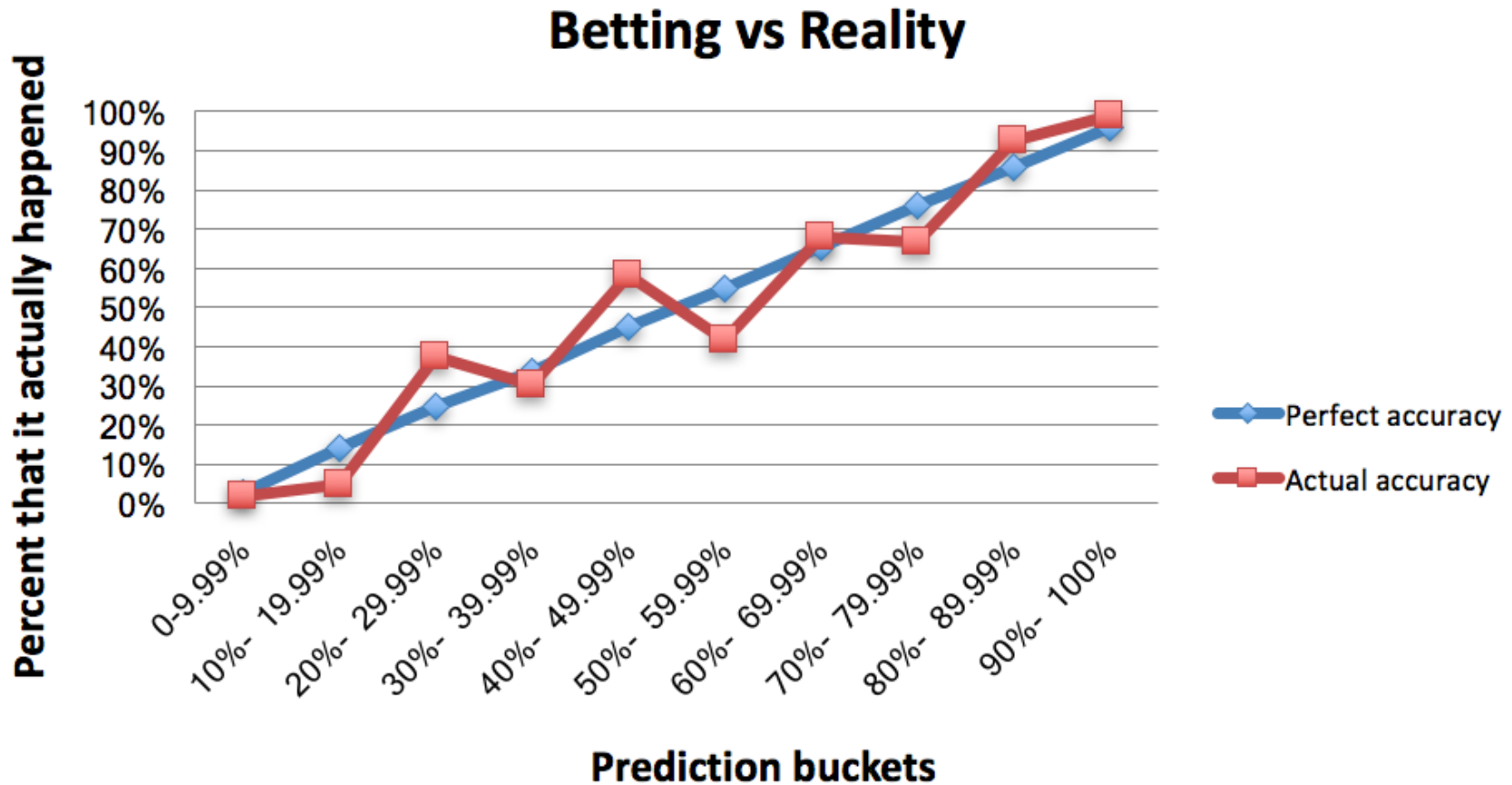
Calibration in Practice

Calibration in Practice



Calibration plots of FiveThirtyEight.com
(as of June 2019)

Calibration in Practice



Calibration plot of ElectionBettingOdds.com
(2016 – 2018)

Example

Example

time	1	2	3	4	5	6	...
------	---	---	---	---	---	---	-----

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
F1	100%	0%	100%	0%	100%	0%	

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
F1	100%	0%	100%	0%	100%	0%	
F2	50%	50%	50%	50%	50%	50%	

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
F1	100%	0%	100%	0%	100%	0%	
F2	50%	50%	50%	50%	50%	50%	

F1: **CALIBRATION** = 0

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
F1	100%	0%	100%	0%	100%	0%	
F2	50%	50%	50%	50%	50%	50%	

F1: **CALIBRATION** = 0

F2: **CALIBRATION** = 0

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
F1	100%	0%	100%	0%	100%	0%	
F2	50%	50%	50%	50%	50%	50%	

F1: **CALIBRATION** = 0 **IN-BIN VARIANCE** = 0

F2: **CALIBRATION** = 0

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
F1	100%	0%	100%	0%	100%	0%	
F2	50%	50%	50%	50%	50%	50%	

F1: **CALIBRATION** = 0 **IN-BIN VARIANCE** = 0

F2: **CALIBRATION** = 0 **IN-BIN VARIANCE** = $\frac{1}{4}$

Notations

Notations

- $a_t =$ action at time t

Notations

- a_t = action at time t
- c_t = forecast at time t

Notations

- a_t = action at time t
- c_t = forecast at time t
- $\bar{a}(x) \equiv \bar{a}_T(x)$ = average of the actions in all periods where the forecast was x

Notations

- a_t = action at time t
- c_t = forecast at time t
- $\bar{a}(x) \equiv \bar{a}_T(x)$ = average of the actions in all periods where the forecast was x

$$\bar{a}(x) = \frac{\sum_{t=1}^T \mathbf{1}_x(c_t) a_t}{\sum_{t=1}^T \mathbf{1}_x(c_t)}$$

Notations

- a_t = action at time t
- c_t = forecast at time t
- $\bar{a}(x) \equiv \bar{a}_T(x)$ = average of the actions in all periods where the forecast was x

Notations

- a_t = action at time t
- c_t = forecast at time t
- $\bar{a}(x) \equiv \bar{a}_T(x)$ = average of the actions in all periods where the forecast was x
- $\mathcal{K} \equiv \mathcal{K}_T$ = **CALIBRATION** score = average distance between c_t and $\bar{a}(c_t)$

Notations

- a_t = action at time t
- c_t = forecast at time t
- $\bar{a}(x) \equiv \bar{a}_T(x)$ = average of the actions in all periods where the forecast was x
- $\mathcal{K} \equiv \mathcal{K}_T$ = **CALIBRATION** score = average distance between c_t and $\bar{a}(c_t)$

$$\mathcal{K} = \frac{1}{T} \sum_{t=1}^T \|c_t - \bar{a}(c_t)\|^2$$

Notations

- a_t = action at time t
- c_t = forecast at time t
- $\bar{a}(x) \equiv \bar{a}_T(x)$ = average of the actions in all periods where the forecast was x
- $\mathcal{K} \equiv \mathcal{K}_T$ = **CALIBRATION** score = average distance between c_t and $\bar{a}(c_t)$

Notations

- a_t = action at time t
- c_t = forecast at time t
- $\bar{a}(x) \equiv \bar{a}_T(x)$ = average of the actions in all periods where the forecast was x
- $\mathcal{K} \equiv \mathcal{K}_T$ = **CALIBRATION** score = average distance between c_t and $\bar{a}(c_t)$
- $\mathcal{R} \equiv \mathcal{R}_T$ = **REFINEMENT** score = average variance inside the bins

Notations

- a_t = action at time t
- c_t = forecast at time t
- $\bar{a}(x) \equiv \bar{a}_T(x)$ = average of the actions in all periods where the forecast was x
- $\mathcal{K} \equiv \mathcal{K}_T$ = **CALIBRATION** score = average distance between c_t and $\bar{a}(c_t)$
- $\mathcal{R} \equiv \mathcal{R}_T$ = **REFINEMENT** score = average variance inside the bins

$$\mathcal{R} = \frac{1}{T} \sum_{t=1}^T \|a_t - \bar{a}(c_t)\|^2$$

Notations

- a_t = action at time t
- c_t = forecast at time t
- $\bar{a}(x) \equiv \bar{a}_T(x)$ = average of the actions in all periods where the forecast was x
- $\mathcal{K} \equiv \mathcal{K}_T$ = **CALIBRATION** score = average distance between c_t and $\bar{a}(c_t)$
- $\mathcal{R} \equiv \mathcal{R}_T$ = **REFINEMENT** score = average variance inside the bins

Brier score

Brier score

- $\mathcal{B} \equiv \mathcal{B}_T = \mathbf{BRIER}$ (1950) score = average distance between a_t and c_t

Brier score

- $\mathcal{B} \equiv \mathcal{B}_T = \mathbf{BRIER}$ (1950) score = average distance between a_t and c_t

$$\mathcal{B} = \frac{1}{T} \sum_{t=1}^T \|a_t - c_t\|^2$$

Brier score

- $\mathcal{B} \equiv \mathcal{B}_T = \mathbf{BRIER}$ (1950) score = average distance between a_t and c_t

Brier score

- $\mathcal{B} \equiv \mathcal{B}_T = \mathbf{BRIER}$ (1950) score = average distance between a_t and c_t



$$\mathcal{B} = \mathcal{R} + \mathcal{K}$$

Brier score

- $\mathcal{B} \equiv \mathcal{B}_T = \text{BRIER}$ (1950) score = average distance between a_t and c_t



$$\mathcal{B} = \mathcal{R} + \mathcal{K}$$

$$\text{BRIER} = \text{REFINEMENT} + \text{CALIBRATION}$$

Brier score

- $\mathcal{B} \equiv \mathcal{B}_T = \text{BRIER}$ (1950) score = average distance between a_t and c_t



$$\mathcal{B} = \mathcal{R} + \mathcal{K}$$

$$\text{BRIER} = \text{REFINEMENT} + \text{CALIBRATION}$$

Proof.

$$\mathbb{E}[(X - c)^2] = \text{Var}(X) + (\bar{X} - c)^2$$

where c is a constant and X is a random variable with $\bar{X} = \mathbb{E}[X]$

Brier score

- $\mathcal{B} \equiv \mathcal{B}_T = \text{BRIER}$ (1950) score = average distance between a_t and c_t



$$\mathcal{B} = \mathcal{R} + \mathcal{K}$$

$$\text{BRIER} = \text{REFINEMENT} + \text{CALIBRATION}$$

Example

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
F1	100%	0%	100%	0%	100%	0%	
F2	50%	50%	50%	50%	50%	50%	

F1: **CALIBRATION** = 0 **IN-BIN VARIANCE** = 0

F2: **CALIBRATION** = 0 **IN-BIN VARIANCE** = $\frac{1}{4}$

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
F1	100%	0%	100%	0%	100%	0%	
F2	50%	50%	50%	50%	50%	50%	

$$F1: \mathcal{K} = 0 \quad \mathcal{R} = 0$$

$$F2: \mathcal{K} = 0 \quad \mathcal{R} = \frac{1}{4}$$

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
F1	100%	0%	100%	0%	100%	0%	
F2	50%	50%	50%	50%	50%	50%	

$$F1: \mathcal{K} = 0 \quad \mathcal{R} = 0 \quad \mathcal{B} = 0$$

$$F2: \mathcal{K} = 0 \quad \mathcal{R} = \frac{1}{4} \quad \mathcal{B} = \frac{1}{4}$$

“Experts”

“Experts”

Testing experts:

“Experts”

Testing experts:

✓ **BRIER** score

“Experts”

Testing experts:

- ✓ **BRIER** score
- ✗ **CALIBRATION** score

“Expertise”

“Expertise”

- Recognize *patterns* and *regularities* in the data

“Expertise”

- Recognize *patterns* and *regularities* in the data
- *Sort* the days into bins that consist of similar days

“Expertise”

- Recognize *patterns* and *regularities* in the data
- *Sort* the days into bins that consist of similar days
- Make the binning as *refined* as possible

“Expertise”

- Recognize *patterns* and *regularities* in the data
- *Sort* the days into bins that consist of similar days
- Make the binning as *refined* as possible



LOW REFINEMENT SCORE

“Expertise” and Calibration

“Expertise” and Calibration

- **CALIBRATION** ($\mathcal{K} \approx 0$) can always be *guaranteed* in the long run

“Expertise” and Calibration

- **CALIBRATION** ($\mathcal{K} \approx 0$) can always be *guaranteed* in the long run
- But: **CALIBRATION** procedures ignore whatever “**EXPERTISE**” one has

“Expertise” and Calibration

- **CALIBRATION** ($\mathcal{K} \approx 0$) can always be *guaranteed* in the long run
- But: **CALIBRATION** procedures ignore whatever **“EXPERTISE”** one has

Question:

Can one **GAIN CALIBRATION**
without **LOSING “EXPERTISE”** ?

“Expertise” and Calibration

- **CALIBRATION** ($\mathcal{K} \approx 0$) can always be *guaranteed* in the long run
- But: **CALIBRATION** procedures ignore whatever “**EXPERTISE**” one has

Question:

Can one **GAIN CALIBRATION**
without **LOSING “EXPERTISE”** ?

- Can one get \mathcal{K} to 0 without increasing \mathcal{R} ?

“Expertise” and Calibration

- **CALIBRATION** ($\mathcal{K} \approx 0$) can always be *guaranteed* in the long run
- But: **CALIBRATION** procedures ignore whatever “**EXPERTISE**” one has

Question:

Can one **GAIN CALIBRATION**
without **LOSING “EXPERTISE”** ?

- Can one get \mathcal{K} to 0 without increasing \mathcal{R} ?
- Can one decrease $\mathcal{B} = \mathcal{R} + \mathcal{K}$ by \mathcal{K} ?

“Expertise” and Calibration

- Can one decrease \mathcal{B} by κ ?

“Expertise” and Calibration

- Can one decrease \mathcal{B} by κ ?
- **Yes:** Replace each forecast c with the corresponding bin average $\bar{a}(c)$

“Expertise” and Calibration

- Can one decrease \mathcal{B} by \mathcal{K} ?
- **Yes:** Replace each forecast c with the corresponding bin average $\bar{a}(c)$
 $\Rightarrow \mathcal{K}' = 0$

“Expertise” and Calibration

- Can one decrease \mathcal{B} by \mathcal{K} ?
- **Yes:** Replace each forecast c with the corresponding bin average $\bar{a}(c)$
 $\Rightarrow \mathcal{K}' = 0 \quad \mathcal{R}' = \mathcal{R}$

“Expertise” and Calibration

- Can one decrease \mathcal{B} by \mathcal{K} ?
- **Yes:** Replace each forecast c with the corresponding bin average $\bar{a}(c)$
 $\Rightarrow \mathcal{K}' = 0 \quad \mathcal{R}' = \mathcal{R} \quad \mathcal{B}' = \mathcal{B} - \mathcal{K}$

“Expertise” and Calibration

- Can one decrease \mathcal{B} by \mathcal{K} ?
- **Yes:** Replace each forecast c with the corresponding bin average $\bar{a}(c)$
 $\Rightarrow \mathcal{K}' = 0 \quad \mathcal{R}' = \mathcal{R} \quad \mathcal{B}' = \mathcal{B} - \mathcal{K}$
- IN RETROSPECT / OFFLINE
(when the $\bar{a}(c)$ are known)


“Expertise” and Calibration

- Can one decrease \mathcal{B} by \mathcal{K} ?
- **Yes:** Replace each forecast c with the corresponding bin average $\bar{a}(c)$
 $\Rightarrow \mathcal{K}' = 0 \quad \mathcal{R}' = \mathcal{R} \quad \mathcal{B}' = \mathcal{B} - \mathcal{K}$
- IN RETROSPECT / OFFLINE
(when the $\bar{a}(c)$ are known)

Question:

Can one do this ONLINE ?



- 
- Consider a forecasting sequence b_t
(in a [finite] set B)

- Consider a forecasting sequence b_t (in a [finite] set B)
- At each time t generate a forecast c_t

- Consider a forecasting sequence b_t (in a [finite] set B)
- At each time t generate a forecast c_t
 - ONLINE: use only b_t and history

- Consider a forecasting sequence b_t (in a [finite] set B)
- At each time t generate a forecast c_t
 - ONLINE: use only b_t and history
 - such that

$$\mathcal{B}^c \leq \mathcal{B}^b - \mathcal{K}^b$$

- Consider a forecasting sequence b_t (in a [finite] set B)
- At each time t generate a forecast c_t
 - ONLINE: use only b_t and history
 - such that

$$\mathcal{B}_T^c \leq \mathcal{B}_T^b - \mathcal{K}_T^b + o(1) \quad \text{as } T \rightarrow \infty$$

for **ALL** sequences a_t and b_t (uniformly)

- Consider a forecasting sequence b_t (in a [finite] set B)
- At each time t generate a forecast c_t
 - ONLINE: use only b_t and history
 - such that

$$\mathcal{B}^c \leq \mathcal{B}^b - \mathcal{K}^b$$

- Consider a forecasting sequence b_t (in a [finite] set B)
- At each time t generate a forecast c_t
 - ONLINE: use only b_t and history
 - such that

$$\underline{\mathcal{B}^c} \leq \mathcal{B}^b - \mathcal{K}^b = \mathcal{R}^b$$

“Calibeating”

- Consider a forecasting sequence b_t (in a [finite] set B)
- At each time t generate a forecast c_t
 - ONLINE: use only b_t and history
 - such that

$$\underline{\mathcal{B}^c} \leq \mathcal{B}^b - \mathcal{K}^b = \mathcal{R}^b$$

c “BEATS” b by b ’s CALIBRATION score

“Calibeating”

- Consider a forecasting sequence b_t (in a [finite] set B)
- At each time t generate a forecast c_t
 - ONLINE: use only b_t and history
 - such that

$$\underline{\mathcal{B}^c} \leq \mathcal{B}^b - \mathcal{K}^b = \mathcal{R}^b$$

c “BEATS” b by b ’s CALIBRATION score

- **GUARANTEED** for **ALL** sequences of actions and forecasts

Example

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
<i>b</i>	80%	40%	80%	40%	80%	40%	

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
b	80%	40%	80%	40%	80%	40%	

b : $\mathcal{K}^b = 0.1$ $\mathcal{R}^b = 0$ $\mathcal{B}^b = 0.1$

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
b	80%	40%	80%	40%	80%	40%	
c	100%	0%	100%	0%	100%	0%	

b : $\mathcal{K}^b = 0.1$ $\mathcal{R}^b = 0$ $\mathcal{B}^b = 0.1$

Example

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
b	80%	40%	80%	40%	80%	40%	
c	100%	0%	100%	0%	100%	0%	

$$b: \mathcal{K}^b = 0.1 \quad \mathcal{R}^b = 0 \quad \mathcal{B}^b = 0.1$$

$$c: \mathcal{K}^c = 0 \quad \mathcal{R}^c = 0 \quad \mathcal{B}^c = 0$$

Calibeating

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
b	80%	40%	80%	40%	80%	40%	
c	100%	0%	100%	0%	100%	0%	

$$b: \mathcal{K}^b = 0.1 \quad \mathcal{R}^b = 0 \quad \mathcal{B}^b = 0.1$$

$$c: \mathcal{K}^c = 0 \quad \mathcal{R}^c = 0 \quad \mathcal{B}^c = 0$$

c calibeats b : $\mathcal{B}^c \leq \mathcal{B}^b - \mathcal{K}^b$

Calibeating

time	1	2	3	4	5	6	...
rain	1	0	1	0	1	0	
b	80%	40%	80%	40%	80%	40%	
c	100%	0%	100%	0%	100%	0%	

$$b: \mathcal{K}^b = 0.1 \quad \mathcal{R}^b = 0 \quad \mathcal{B}^b = 0.1$$

$$c: \mathcal{K}^c = 0 \quad \mathcal{R}^c = 0 \quad \mathcal{B}^c = 0$$

c calibeats b : $\mathcal{B}^c \leq \mathcal{B}^b - \mathcal{K}^b = \mathcal{R}^b$

Calibrating

Calibrating

(that was easy ...)

Calibeating

(that was easy ...)

*Can one **CALIBEAT** in general, non-stationary, situations ?*

Calibeating

(that was easy ...)

*Can one **CALIBEAT** in general, non-stationary, situations ?*

- **Weather** is arbitrary and not stationary

Calibeating

(that was easy ...)

*Can one **CALIBEAT** in general, non-stationary, situations ?*

- **Weather** is arbitrary and not stationary
- **Forecasts of b** are arbitrary

Calibeating

(that was easy ...)

*Can one **CALIBEAT** in general, non-stationary, situations ?*

- **Weather** is arbitrary and not stationary
- **Forecasts of b** are arbitrary
- **Binning of b** is not perfect ($\mathcal{R}^b > 0$)

Calibeating

(that was easy ...)

*Can one **CALIBEAT** in general, non-stationary, situations ?*

- **Weather** is arbitrary and not stationary
- **Forecasts of b** are arbitrary
- **Binning of b** is not perfect ($\mathcal{R}^b > 0$)
- **Bin averages** do not converge

Calibeating

(that was easy ...)

*Can one **CALIBEAT** in general, non-stationary, situations ?*

- **Weather** is arbitrary and not stationary
- **Forecasts of b** are arbitrary
- **Binning of b** is not perfect ($\mathcal{R}^b > 0$)
- **Bin averages** do not converge
- **ONLINE**

Calibeating

(that was easy ...)

*Can one **CALIBEAT** in general, non-stationary, situations ?*

- **Weather** is arbitrary and not stationary
- **Forecasts of b** are arbitrary
- **Binning of b** is not perfect ($\mathcal{R}^b > 0$)
- **Bin averages** do not converge
- **ONLINE**
- **GUARANTEED** (even against adversary)

Calibrating

Calibrating

Theorem

There exists a **CALIBEATING** procedure

A Way to Calibeat

A Way to Calibeat

Theorem

The procedure

$$c_t = \bar{a}_{t-1}^b(b_t)$$

GUARANTEES b-CALIBEATING



A Simple Way to Calibeat

Theorem

The procedure

$$c_t = \bar{a}_{t-1}^b(b_t)$$

GUARANTEES b-CALIBEATING

**Forecast the average action
of the current b -forecast**



Proof

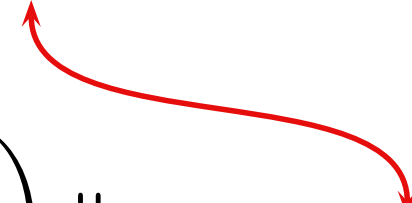
Proof

$$\text{Var} = \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_T\|^2$$

Proof

$$\begin{aligned}\text{Var} &= \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_T\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \left(1 - \frac{1}{t}\right) \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2\end{aligned}$$

Proof

$$\begin{aligned}\text{Var} &= \frac{1}{T} \sum_{t=1}^T \|x_t - \bar{x}_T\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \left(1 - \frac{1}{t}\right) \|x_t - \bar{x}_{t-1}\|^2\end{aligned}$$


Proof

$$\begin{aligned}\text{Var} &= \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_T\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \left(1 - \frac{1}{t}\right) \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2\end{aligned}$$

Proof

$$\begin{aligned}\text{Var} &= \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_T\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \left(1 - \frac{1}{t}\right) \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2 - \mathbf{o}(1)\end{aligned}$$

Proof

$$\begin{aligned}\text{Var} &= \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_T\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \left(1 - \frac{1}{t}\right) \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2 - \mathbf{o}(1)\end{aligned}$$

$$(*) \quad \mathbf{o}(1) = \mathbf{O}\left(\frac{1}{T} \sum_{t=1}^T \frac{1}{t}\right) = \mathbf{O}\left(\frac{\log T}{T}\right)$$

Proof

$$\begin{aligned}\text{Var} &= \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_T\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \left(1 - \frac{1}{t}\right) \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2 - o(1)\end{aligned}$$

Proof: “Online Variance”

$$\begin{aligned}\text{Var} &= \frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_T\|^2 \\ &= \frac{1}{T} \sum_{t=1}^T \left(1 - \frac{1}{t}\right) \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2 \\ &= \underbrace{\frac{1}{T} \sum_{t=1}^T \|\mathbf{x}_t - \bar{\mathbf{x}}_{t-1}\|^2}_{\widetilde{\text{Var}}} - o(1) \\ &= \widetilde{\text{Var}} - o(1)\end{aligned}$$

Proof: “Online Variance”

$$\text{Var} = \widetilde{\text{Var}} - o(1)$$

Proof: “Online Refinement”

$$\text{Var} = \widetilde{\text{Var}} - o(1)$$

$$\mathcal{R}^b = \widetilde{\mathcal{R}}^b - o(1)$$

Proof: “Online Refinement”

$$\text{Var} = \widetilde{\text{Var}} - o(1)$$

$$\mathcal{R}^b = \widetilde{\mathcal{R}}^b - o(1)$$

$$= \frac{1}{T} \sum_{t=1}^T \|a_t - \bar{a}_{t-1}(b_t)\|^2 - o(1)$$

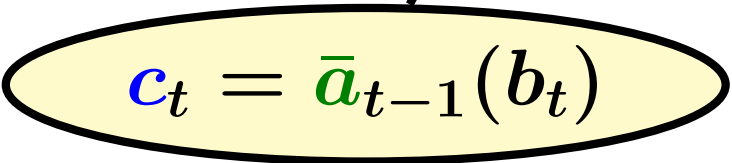
Proof: “Online Refinement”

$$\text{Var} = \widetilde{\text{Var}} - o(1)$$

$$\mathcal{R}^b = \widetilde{\mathcal{R}}^b - o(1)$$

$$= \frac{1}{T} \sum_{t=1}^T \|a_t - \bar{a}_{t-1}(b_t)\|^2 - o(1)$$

$$\underbrace{\hspace{15em}}_{\mathcal{B}^c} - o(1)$$


$$c_t = \bar{a}_{t-1}(b_t)$$

Calibrating

Calibeating

Theorem

$$c_t = \bar{a}_{t-1}^b(b_t)$$

GUARANTEES b-CALIBEATING:

$$\underline{\mathcal{B}^c} \leq \mathcal{B}^b - \mathcal{K}^b$$

Self-Calibrating

Theorem

$$c_t = \bar{a}_{t-1}^b(b_t)$$

GUARANTEES **b-CALIBEATING**:

$$\underline{\mathcal{B}}^c \leq \mathcal{B}^b - \mathcal{K}^b$$

Theorem

$$c_t = \bar{a}_{t-1}^c(c_t)$$

GUARANTEES **c-CALIBEATING**:

$$\underline{\mathcal{B}}^c \leq \mathcal{B}^c - \mathcal{K}^c$$

Self-Calibrating

Theorem

$$c_t = \bar{a}_{t-1}^b(b_t)$$

GUARANTEES **b-CALIBEATING**:

$$\underline{\mathcal{B}}^c \leq \mathcal{B}^b - \mathcal{K}^b$$

Theorem

$$c_t = \bar{a}_{t-1}^c(c_t)$$

GUARANTEES **c-CALIBEATING**:

$$\begin{aligned} \mathcal{B}^c &\leq \mathcal{B}^c - \mathcal{K}^c \\ \Leftrightarrow \mathcal{K}^c &= 0 \end{aligned}$$

Self-Calibrating = Calibrating

Theorem

$$c_t = \bar{a}_{t-1}^b(b_t)$$

GUARANTEES b-CALIBEATING:

$$\underline{\mathcal{B}}^c \leq \mathcal{B}^b - \mathcal{K}^b$$

Theorem

$$c_t = \bar{a}_{t-1}^c(c_t)$$

GUARANTEES CALIBRATION:

$$\begin{aligned} \mathcal{B}^c &\leq \mathcal{B}^c - \mathcal{K}^c \\ \Leftrightarrow \mathcal{K}^c &= 0 \end{aligned}$$

“Fixed Point”

How do we get c_t “close to” $\bar{a}_{t-1}(c_t)$?

“Fixed Point”

How do we get c_t “close to” $\bar{a}_{t-1}(c_t)$?

- $C \subset \mathbb{R}^m$ compact convex set
- $D \subset C$ finite δ -grid of C (for $\delta > 0$)
- $f : D \rightarrow \mathbb{R}^m$ **arbitrary** function

“Fixed Point”

How do we get c_t “close to” $\bar{a}_{t-1}(c_t)$?

- $C \subset \mathbb{R}^m$ compact convex set
- $D \subset C$ finite δ -grid of C (for $\delta > 0$)
- $f : D \rightarrow \mathbb{R}^m$ **arbitrary** function

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

“Fixed Point”

How do we get \mathbf{c}_t “close to” $\bar{\mathbf{a}}_{t-1}(\mathbf{c}_t)$?

- $C \subset \mathbb{R}^m$ compact convex set
- $D \subset C$ finite δ -grid of C (for $\delta > 0$)
- $f : D \rightarrow \mathbb{R}^m$ **arbitrary** function

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|\mathbf{v} - \mathbf{x}\|^2 \right] \leq \mathbb{E}_{x \sim P} \left[\|\mathbf{v} - f(\mathbf{x})\|^2 \right] + \delta^2$$

$$\forall \mathbf{v} \in C$$

Stochastic “Fixed Point”

How do we get \mathbf{c}_t “close to” $\bar{\mathbf{a}}_{t-1}(\mathbf{c}_t)$?

- $C \subset \mathbb{R}^m$ compact convex set
- $D \subset C$ finite δ -grid of C (for $\delta > 0$)
- $f : D \rightarrow \mathbb{R}^m$ **arbitrary** function

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|\mathbf{v} - \mathbf{x}\|^2 \right] \leq \mathbb{E}_{x \sim P} \left[\|\mathbf{v} - f(\mathbf{x})\|^2 \right] + \delta^2$$

$$\forall \mathbf{v} \in C$$

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 \right] \leq \mathbb{E}_{x \sim P} \left[\|v - f(x)\|^2 \right] + \delta^2$$

$$\forall v \in C$$

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

Proof.

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

Proof.

• wlog (project $f(x)$ to C): $f : D \rightarrow C$

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

Proof.

- wlog (project $f(x)$ to C): $f : D \rightarrow C$
- interpolate: *continuous* $f : C \rightarrow C$

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

Proof.

- wlog (project $f(x)$ to C): $f : D \rightarrow C$
- interpolate: *continuous* $f : C \rightarrow C$
- apply Brouwer **FIXED POINT** theorem

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

Proof.

- wlog (project $f(x)$ to C): $f : D \rightarrow C$
- interpolate: *continuous* $f : C \rightarrow C$
- apply Brouwer **FIXED POINT** theorem

“Wrong” Proof !

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

“Right” Proof.

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

“Right” Proof. Use the **MINIMAX** theorem

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

“Right” Proof. Use the **MINIMAX** theorem

• $h(x, v) := \|v - x\|^2 - \|v - f(x)\|^2$

Stochastic “Fixed Point”

- $h(x, v) := \|v - x\|^2 - \|v - f(x)\|^2$

Stochastic “Fixed Point”

- $h(x, v) := \|v - x\|^2 - \|v - f(x)\|^2$
- For every distribution Q on $v \in C$:

Stochastic “Fixed Point”

- $h(\mathbf{x}, \mathbf{v}) := \|\mathbf{v} - \mathbf{x}\|^2 - \|\mathbf{v} - \mathbf{f}(\mathbf{x})\|^2$

- For every distribution Q on $\mathbf{v} \in C$:

$$h(\mathbf{x}, Q) = \mathbb{E}_{\mathbf{v} \sim Q} \left[\|\mathbf{v} - \mathbf{x}\|^2 - \|\mathbf{v} - \mathbf{f}(\mathbf{x})\|^2 \right]$$

Stochastic “Fixed Point”

- $h(\mathbf{x}, \mathbf{v}) := \|\mathbf{v} - \mathbf{x}\|^2 - \|\mathbf{v} - \mathbf{f}(\mathbf{x})\|^2$

- For every distribution Q on $\mathbf{v} \in C$:

$$h(\mathbf{x}, Q) = \mathbb{E}_{\mathbf{v} \sim Q} \left[\|\mathbf{v} - \mathbf{x}\|^2 - \|\mathbf{v} - \mathbf{f}(\mathbf{x})\|^2 \right]$$

- For $\mathbf{x} = \mathbb{E}_Q[\mathbf{v}]$ we get $h(\mathbf{x}, Q) \leq 0$

Stochastic “Fixed Point”

- $h(\mathbf{x}, \mathbf{v}) := \|\mathbf{v} - \mathbf{x}\|^2 - \|\mathbf{v} - \mathbf{f}(\mathbf{x})\|^2$

- For every distribution Q on $\mathbf{v} \in C$:

$$h(\mathbf{x}, Q) = \mathbb{E}_{\mathbf{v} \sim Q} \left[\|\mathbf{v} - \mathbf{x}\|^2 - \|\mathbf{v} - \mathbf{f}(\mathbf{x})\|^2 \right]$$

- For $\mathbf{x} = \mathbb{E}_Q [\mathbf{v}]$ we get $h(\mathbf{x}, Q) \leq 0$

- For $\mathbf{x} \approx \mathbb{E}_Q [\mathbf{v}]$ in D we get $h(\mathbf{x}, Q) \leq \delta^2$

Stochastic “Fixed Point”

- $h(\mathbf{x}, \mathbf{v}) := \|\mathbf{v} - \mathbf{x}\|^2 - \|\mathbf{v} - \mathbf{f}(\mathbf{x})\|^2$
- For every distribution Q on $\mathbf{v} \in C$:
 - For $\mathbf{x} \approx \mathbb{E}_Q[\mathbf{v}]$ in D we get $h(\mathbf{x}, Q) \leq \delta^2$

Stochastic “Fixed Point”

- $h(\mathbf{x}, \mathbf{v}) := \|\mathbf{v} - \mathbf{x}\|^2 - \|\mathbf{v} - \mathbf{f}(\mathbf{x})\|^2$
- For every distribution Q on $\mathbf{v} \in C$:
 - For $\mathbf{x} \approx \mathbb{E}_Q[\mathbf{v}]$ in D we get $h(\mathbf{x}, Q) \leq \delta^2$
- \Rightarrow [MINIMAX]
There exists a distribution P on $\mathbf{x} \in D$ s.t.
$$h(P, \mathbf{v}) \leq \delta^2 \quad \text{for every } \mathbf{v} \in C$$

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

- **Obtained by solving a MINIMAX problem (LP)**

Outgoing Minimax (FH)

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

- **Obtained by solving a MINIMAX problem (LP)**

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

- **Obtained by solving a MINIMAX problem (LP)**

Stochastic “Fixed Point”

Theorem. There exists a probability distribution P on the δ -grid D of C such that:

$$\mathbb{E}_{x \sim P} \left[\|v - x\|^2 - \|v - f(x)\|^2 \right] \leq \delta^2 \quad \forall v \in C$$

- **Obtained by solving a MINIMAX problem (LP)**
- Moreover: solving a **FIXED POINT** problem yields a probability distribution P that is **ALMOST DETERMINISTIC**: its support is included in a ball of size δ

Calibrating

Calibrating

Theorem

There is a stochastic procedure
that **GUARANTEES CALIBRATION**

Calibrating

Theorem

There is a stochastic procedure
that **GUARANTEES CALIBRATION**

Proof. Self-calibrating + Stochastic Fixed Point

Calibrating

Theorem

There is a stochastic procedure
that **GUARANTEES CALIBRATION**

Proof. Self-calibrating + Stochastic Fixed Point

Note. δ -**CALIBRATION**

Calibrated Calibeating

Calibrated Calibeating

Theorem

There is a stochastic procedure
that **GUARANTEES CALIBEATING**

Calibrated Calibeating

Theorem

There is a stochastic procedure
that **GUARANTEES CALIBEATING**
and **CALIBRATION**

Calibrated Calibeating

Theorem

There is a stochastic procedure that **GUARANTEES CALIBEATING** and **CALIBRATION**

Proof. Calibeat the **joint** binning of b and c , by applying Stochastic Fixed Point

Calibrated Calibeating

Theorem

There is a stochastic procedure that **GUARANTEES CALIBEATING** and **CALIBRATION**

Proof. Calibeat the **joint** binning of b and c , by applying Stochastic Fixed Point

STRONG CALIBEATING:

$$\mathcal{R}(c) \leq \mathcal{R}(b) \quad \text{and} \quad \mathcal{K}(c) = 0$$

Continuous Calibration

Continuous Calibration

- **CONTINUOUS CALIBRATION**: combine the days when the forecast was *close to p*

Continuous Calibration

- **CONTINUOUS CALIBRATION**: combine the days when the forecast was *close to p* (smooth out the calibration score)

Continuous Calibration

- **CONTINUOUS CALIBRATION**: combine the days when the forecast was *close to p* (smooth out the calibration score)
- **Theorem:**

There exists a *deterministic* procedure that is **CONTINUOUSLY CALIBRATED**.

Continuous Calibration

- **CONTINUOUS CALIBRATION**: combine the days when the forecast was *close to p* (smooth out the calibration score)
- **Theorem**:

There exists a *deterministic* procedure that is **CONTINUOUSLY CALIBRATED**.

Deterministic \Rightarrow holds also when the forecasts are “*leaked*”

Continuous Calibration

- **CONTINUOUS CALIBRATION**: combine the days when the forecast was *close to p* (smooth out the calibration score)
- **Theorem**:

There exists a *deterministic* procedure that is **CONTINUOUSLY CALIBRATED**.

Deterministic \Rightarrow holds also when the forecasts are “*leaked*”

Foster and Kakade (2004, 2006)
Foster and Hart (2018, **2021**)

Continuous-Calibrated Calibeating

Continuous-Calibrated Calibeating

Theorem

There is a *deterministic* procedure
that **GUARANTEES CALIBEATING**

Continuous-Calibrated Calibeating

Theorem

There is a *deterministic* procedure
that **GUARANTEES CALIBEATING**
and **CONTINUOUS CALIBRATION**

Continuous-Calibrated Calibeating

Theorem

There is a *deterministic* procedure
that **GUARANTEES CALIBEATING**
and **CONTINUOUS CALIBRATION**

Proof. Calibeat the **joint** binning of b and c ,
by a Fixed Point result (Brouwer)

Multi-Calibeating

Multi-Calibeating

Theorem

There is a *deterministic* procedure
that **GUARANTEES**
simultaneous CALIBEATING
of several forecasters

Multi-Calibeating

Theorem

There is a *stochastic* procedure
that **GUARANTEES**
simultaneous CALIBEATING
of several forecasters
and **CALIBRATION**

Multi-Calibeating

Theorem

There is a *stochastic* procedure
that **GUARANTEES**
simultaneous CALIBEATING
of several forecasters
and **CALIBRATION**

Proof. Calibeat the **joint** binning



In all the results above:

In all the results above:

	CALIBRATION	
Obtained by	<i>Minimax</i>	
Procedure	<i>stochastic</i>	

... and Continuous Calibration

In all the results above:

	CALIBRATION	CONTINUOUS CALIBRATION
Obtained by	<i>Minimax</i>	<i>Fixed Point</i>
Procedure	<i>stochastic</i>	<i>deterministic</i>

Refinement Score and Brier Score

Refinement Score and Brier Score

Claim. The **REFINEMENT** score is the *minimal* **BRIER** score over all *relabelings of the bins*:

Refinement Score and Brier Score

Claim. The **REFINEMENT** score is the *minimal BRIER* score over all *relabelings of the bins*:

$$\mathcal{R}_T(\mathbf{b}) = \min_{\phi} \mathcal{B}_T(\phi(\mathbf{b}))$$

Refinement Score and Brier Score

Claim. The **REFINEMENT** score is the *minimal BRIER* score over all *relabelings of the bins*:

$$\mathcal{R}_T(\mathbf{b}) = \min_{\phi} \mathcal{B}_T(\phi(\mathbf{b}))$$

where the minimum is taken over all

$$\phi : B \rightarrow \Delta(A)$$

and

$$\phi(\mathbf{b}) \equiv (\phi(b_1), \dots, \phi(b_T))$$

Refinement Score and Brier Score

Claim. The **REFINEMENT** score is the *minimal BRIER* score over all *relabelings of the bins*:

$$\mathcal{R}_T(\mathbf{b}) = \min_{\phi} \mathcal{B}_T(\phi(\mathbf{b}))$$

where the minimum is taken over all

$$\phi : B \rightarrow \Delta(A)$$

and

$$\phi(\mathbf{b}) \equiv (\phi(b_1), \dots, \phi(b_T))$$

Proof. Label each bin b with $\phi(b) = \bar{a}_T(b)$

Calibrating

Calibrating

• **c** CALIBEATS **b**:

$$\mathcal{B}_T(\mathbf{c}) \leq \mathcal{R}_T(\mathbf{b}) + o(1)$$

Calibrating

• **c** CALIBEATS **b**:

$$\mathcal{B}(c) \leq \mathcal{R}(b)$$

Calibrating

• **c** CALIBEATS **b**:

$$\mathcal{B}(c) \leq \mathcal{R}(b)$$

$$\mathcal{B}(c) \leq \min_{\phi} \mathcal{B}(\phi(b))$$

where $\phi : B \rightarrow \Delta(A)$

Calibrating

- **c CALIBEATS b:**

$$\mathcal{B}(c) \leq \mathcal{R}(b)$$

$$\mathcal{B}(c) \leq \min_{\phi} \mathcal{B}(\phi(b))$$

where $\phi : B \rightarrow \Delta(A)$

- **c MULTI-CALIBEATS b_1, \dots, b_N :**

$$\mathcal{B}(c) \leq \min_{1 \leq n \leq N} \min_{\phi^n} \mathcal{B}(\phi^n(b^n))$$

Calibeating

- **c CALIBEATS b:**

$$\mathcal{B}(c) \leq \mathcal{R}(b)$$

$$\mathcal{B}(c) \leq \min_{\phi} \mathcal{B}(\phi(b))$$

where $\phi : B \rightarrow \Delta(A)$

- **c MULTI-CALIBEATS b_1, \dots, b_N :**

$$\mathcal{B}(c) \leq \min_{1 \leq n \leq N} \min_{\phi^n} \mathcal{B}(\phi^n(b^n))$$

where $\phi^n : B^n \rightarrow \Delta(A)$

Calibrating

- **c** MULTI-CALIBEATS $\mathbf{b}_1, \dots, \mathbf{b}_N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{1 \leq n \leq N} \min_{\phi^n} \mathcal{B}(\phi^n(\mathbf{b}^n))$$

where $\phi^n : B^n \rightarrow \Delta(A)$

Calibeating

- **c** MULTI-CALIBEATS $\mathbf{b}^1, \dots, \mathbf{b}^N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{1 \leq n \leq N} \min_{\phi^n} \mathcal{B}(\phi^n(\mathbf{b}^n))$$

where $\phi^n : B^n \rightarrow \Delta(A)$

Calibeating

- **c MULTI-CALIBEATS** $\mathbf{b}^1, \dots, \mathbf{b}^N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{1 \leq n \leq N} \min_{\phi^n} \mathcal{B}(\phi^n(\mathbf{b}^n))$$

where $\phi^n : B^n \rightarrow \Delta(A)$

- **c CALIBEATS THE JOINT** of $\mathbf{b}^1, \dots, \mathbf{b}^N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{\phi} \mathcal{B}(\phi(\mathbf{b}^1, \dots, \mathbf{b}^N))$$

Calibeating

- **c** MULTI-CALIBEATS $\mathbf{b}^1, \dots, \mathbf{b}^N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{1 \leq n \leq N} \min_{\phi^n} \mathcal{B}(\phi^n(\mathbf{b}^n))$$

where $\phi^n : B^n \rightarrow \Delta(A)$

- **c** CALIBEATS THE JOINT of $\mathbf{b}^1, \dots, \mathbf{b}^N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{\phi} \mathcal{B}(\phi(\mathbf{b}^1, \dots, \mathbf{b}^N))$$

where $\phi : B^1 \times \dots \times B^N \rightarrow \Delta(A)$

Stronger Expert

Stronger Expert

- **c** is AS STRONG AS b^1, \dots, b^N :

$$\mathcal{B}(c) \leq \min_{1 \leq n \leq N} \mathcal{B}(b^n)$$

Stronger Expert

- **c** is AS STRONG AS b^1, \dots, b^N :

$$\mathcal{B}(c) \leq \min_{1 \leq n \leq N} \mathcal{B}(b^n)$$

- **c** is AS STRONG AS THE LINEAR SPAN of b^1, \dots, b^N if

$$\mathcal{B}(c) \leq \min_{w^1, \dots, w^N} \mathcal{B}(w^1 b^1 + \dots + w^N b^N)$$

Calibrating vs Stronger Expert

Calibeating vs Stronger Expert

- **c** MULTI-CALIBEATS $\mathbf{b}_1, \dots, \mathbf{b}_N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{1 \leq n \leq N} \min_{\phi^n} \mathcal{B}(\phi^n(\mathbf{b}^n))$$

where $\phi^n : B^n \rightarrow \Delta(A)$

Calibeating vs Stronger Expert

- **c** MULTI-CALIBEATS $\mathbf{b}_1, \dots, \mathbf{b}_N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{1 \leq n \leq N} \min_{\phi^n} \mathcal{B}(\phi^n(\mathbf{b}^n))$$

where $\phi^n : B^n \rightarrow \Delta(A)$

- **c** is AS STRONG AS $\mathbf{b}^1, \dots, \mathbf{b}^N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{1 \leq n \leq N} \mathcal{B}(\mathbf{b}^n)$$

Calibeating \succ Stronger Expert

- c **MULTI-CALIBEATS** b_1, \dots, b_N :

$$\mathcal{B}(c) \leq \min_{1 \leq n \leq N} \min_{\phi^n} \mathcal{B}(\phi^n(b^n))$$

where $\phi^n : B^n \rightarrow \Delta(A)$

- c is **AS STRONG AS** b^1, \dots, b^N :

$$\mathcal{B}(c) \leq \min_{1 \leq n \leq N} \mathcal{B}(b^n)$$

CALIBEATING is *stronger* !

Calibrating vs Stronger Expert

Calibrating vs Stronger Expert

- **c** CALIBEATS THE JOINT of $\mathbf{b}_1, \dots, \mathbf{b}_N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{\phi} \mathcal{B}(\phi(\mathbf{b}^1, \dots, \mathbf{b}^N))$$

where $\phi : B^1 \times \dots \times B^N \rightarrow \Delta(A)$

Calibrating vs Stronger Expert

- **c** CALIBEATS THE JOINT of $\mathbf{b}_1, \dots, \mathbf{b}_N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{\phi} \mathcal{B}(\phi(\mathbf{b}^1, \dots, \mathbf{b}^N))$$

where $\phi : B^1 \times \dots \times B^N \rightarrow \Delta(A)$

- **c** is AS STRONG AS THE LINEAR SPAN of $\mathbf{b}^1, \dots, \mathbf{b}^N$ if

$$\mathcal{B}(\mathbf{c}) \leq \min_{w^1, \dots, w^N} \mathcal{B}(w^1 \mathbf{b}^1 + \dots + w^N \mathbf{b}^N)$$

Calibrating \succ Stronger Expert

- **c CALIBEATS THE JOINT** of $\mathbf{b}_1, \dots, \mathbf{b}_N$:

$$\mathcal{B}(\mathbf{c}) \leq \min_{\phi} \mathcal{B}(\phi(\mathbf{b}^1, \dots, \mathbf{b}^N))$$

where $\phi : B^1 \times \dots \times B^N \rightarrow \Delta(A)$

- **c is AS STRONG AS THE LINEAR SPAN** of $\mathbf{b}^1, \dots, \mathbf{b}^N$ if

$$\mathcal{B}(\mathbf{c}) \leq \min_{w^1, \dots, w^N} \mathcal{B}(w^1 \mathbf{b}^1 + \dots + w^N \mathbf{b}^N)$$

CALIBEATING is stronger !

Scoring Rules

Scoring Rules

- **SCORING RULE:** quadratic loss $\mathbb{E}_a[\|a - c\|^2]$

Scoring Rules

- **SCORING RULE:** quadratic loss $\mathbb{E}_a[\|a - c\|^2]$
- minimal when $c =$ distribution of $a \quad =: d$

Scoring Rules

- **SCORING RULE**: quadratic loss $\mathbb{E}_a[\|a - c\|^2]$
 - minimal when $c =$ distribution of $a =: d$
- **PROPER** scoring rule L :
 - expected loss is minimized when the forecast is correct, i.e., $c = d$

Scoring Rules

- **SCORING RULE**: quadratic loss $\mathbb{E}_a[\|a - c\|^2]$
 - minimal when $c =$ distribution of $a =: d$
- **PROPER** scoring rule L :
 - expected loss is minimized when the forecast is correct, i.e., $c = d$
 - \rightarrow **DIVERGENCE** $D \equiv D^L$
 $D(d, c) \geq 0$ and $D(d, d) = 0$
(replaces $\| \cdot \|^2$)

Scoring Rules

- **SCORING RULE**: quadratic loss $\mathbb{E}_a[\|a - c\|^2]$
 - minimal when $c =$ distribution of $a =: d$
- **PROPER** scoring rule L :
 - expected loss is minimized when the forecast is correct, i.e., $c = d$
 - \rightarrow **DIVERGENCE** $D \equiv D^L$
 $D(d, c) \geq 0$ and $D(d, d) = 0$
(replaces $\| \cdot \|^2$)
 - smooth: Lipschitz-continuous

Brier, Calibration, Refinement

Brier, Calibration, Refinement

$$\mathcal{B}_T^L := \frac{1}{T} \sum_{t=1}^T D^L(a_t, c_t)$$

Brier, Calibration, Refinement

$$\mathcal{B}_T^L := \frac{1}{T} \sum_{t=1}^T D^L(\mathbf{a}_t, \mathbf{c}_t)$$

$$\mathcal{K}_T^L := \frac{1}{T} \sum_{t=1}^t D^L(\bar{\mathbf{a}}_T(\mathbf{c}_t), \mathbf{c}_t)$$

Brier, Calibration, Refinement

$$\mathcal{B}_T^L := \frac{1}{T} \sum_{t=1}^T D^L(\mathbf{a}_t, \mathbf{c}_t)$$

$$\mathcal{K}_T^L := \frac{1}{T} \sum_{t=1}^t D^L(\bar{\mathbf{a}}_T(\mathbf{c}_t), \mathbf{c}_t)$$

$$\mathcal{R}_T^L := \frac{1}{T} \sum_{t=1}^T D^L(\mathbf{a}_t, \bar{\mathbf{a}}_T(\mathbf{c}_t))$$

Proper Calibration / Calibeating

Proper Calibration / Calibeating

- **PROPER CALIBRATION / CALIBEATING:**
calibration / calibeating w.r.t. all proper
Lipschitz scoring rules L

Proper Calibration / Calibeating

- **PROPER CALIBRATION / CALIBEATING:**
calibration / calibeating w.r.t. all proper
Lipschitz scoring rules L (uniformly in L)

Proper Calibration / Calibeating

- **PROPER CALIBRATION / CALIBEATING:**
calibration / calibeating w.r.t. all proper Lipschitz scoring rules L (uniformly in L)
- **PROPER-CALIBRATION:**

$$\sup_L \sup_a \mathbb{E} [\mathcal{K}_T^L(c)] \leq o(1) \quad (\text{as } T \rightarrow \infty)$$

Proper Calibration / Calibeating

- **PROPER CALIBRATION / CALIBEATING:**
calibration / calibeating w.r.t. all proper Lipschitz scoring rules L (uniformly in L)

- **PROPER-CALIBRATION:**

$$\sup_L \sup_a \mathbb{E} [\mathcal{K}_T^L(c)] \leq o(1) \quad (\text{as } T \rightarrow \infty)$$

- **PROPER-CALIBEATING:**

$$\sup_L \sup_{a,b} \mathbb{E} [\mathcal{B}_T^L(c) - \mathcal{R}_T^L(b)] \leq o(1)$$

(as $T \rightarrow \infty$)

Proper Calibration / Calibeating

Proper Calibration / Calibeating

Results

Proper Calibration / Calibeating

Results

1. Calibration \Rightarrow **PROPER-CALIBRATION**



Proper Calibration / Calibeating

Results

1. Calibration \Rightarrow **PROPER-CALIBRATION**
2. Calibeating \Rightarrow **PROPER-CALIBEATING**

Proper Calibration / Calibeating

Results

1. Calibration  **PROPER-CALIBRATION**
2. Calibeating  **PROPER-CALIBEATING**

Proper Calibration / Calibeating

Results

1. Calibration \Rightarrow **PROPER-CALIBRATION**
2. Calibeating $\not\Rightarrow$ **PROPER-CALIBEATING**
3. “A simple way to calibeat” ($c_t = \bar{a}_{t-1}^b$) is **PROPER-CALIBEATING**

Proper Calibration / Calibeating

Results

1. Calibration \Rightarrow **PROPER-CALIBRATION**
2. Calibeating $\not\Rightarrow$ **PROPER-CALIBEATING**
3. “A simple way to calibeat” ($c_t = \bar{a}_{t-1}^b$) is **PROPER-CALIBEATING**
4. Calibeating the joint is **PROPER-CALIBEATING**

Proper Calibration / Calibeating

Results

1. Calibration \Rightarrow **PROPER-CALIBRATION**
2. Calibeating $\not\Rightarrow$ **PROPER-CALIBEATING**
3. “A simple way to calibeat” ($c_t = \bar{a}_{t-1}^b$) is **PROPER-CALIBEATING**
4. Calibeating the joint is **PROPER-CALIBEATING**
5. **CONTINUOUS PROPER-CALIBEATING** by a deterministic procedure

Proper Calibration / Calibeating

Results

1. Calibration \Rightarrow **PROPER-CALIBRATION**
2. Calibeating $\not\Rightarrow$ **PROPER-CALIBEATING**
3. “A simple way to calibeat” ($c_t = \bar{a}_{t-1}^b$) is **PROPER-CALIBEATING**
4. Calibeating the joint is **PROPER-CALIBEATING**
5. **CONTINUOUS PROPER-CALIBEATING** by a deterministic procedure
6. **PROPER-MULTICALIBEATING**





***What does every forecaster
deserve ?***



*What does every forecaster
deserve ?*

A PROPER CALIBEATING



***What does every forecaster
deserve ?***

A PROPER CALIBEATING