$$\mathrm{dyn}_{f\,\mathring{,}\,g} : [\mathbf{U}_f \, ; \, \mathbf{X}_f \, ; \, \mathbf{X}_g] \longrightarrow [\mathbf{X}_f \, ; \, \mathbf{X}_g],$$

$$[u \, ; \, x_f \, ; \, x_g] \longmapsto [\mathrm{dyn}_f(u, x_f) \, ; \, \mathrm{dyn}_g(\mathrm{ro}_f(x_f), x_g)].$$