$$\mathrm{dyn}_{f\,\fatsemi\,g} : \mathbf{U}_f \times (\mathbf{X}_f \mathbin{\mathring{\fatsemi}} \mathbf{X}_g) \longrightarrow (\mathbf{X}_f \mathbin{\mathring{\fatsemi}} \mathbf{X}_g)$$

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