$$\operatorname{ro}_{f_{\S}(g_{\S}h)}: \mathbf{X}_{f}; (\mathbf{X}_{g}; \mathbf{X}_{h}) \to \mathbf{Y}_{h}$$

$$[x_{f}; x_{g}; x_{h}] \mapsto \operatorname{ro}_{h}(x_{h}).$$