

$$\text{dyn}_{f;g} : \mathbf{U}_f \times (\mathbf{X}_f ; \mathbf{X}_g) \longrightarrow (\mathbf{X}_f ; \mathbf{X}_g)$$

$$\langle u, [x_f ; x_g] \rangle \mapsto [\text{dyn}_f(u, x_f) ; \text{dyn}_g(\text{ro}_f(x_f), x_g)],$$