

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

$$\langle u, \langle x_f, x_g \rangle \rangle \longmapsto \langle \text{dyn}_f(u, x_f), \text{dyn}_g(\text{ro}_f(x_f), x_g) \rangle,$$