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

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