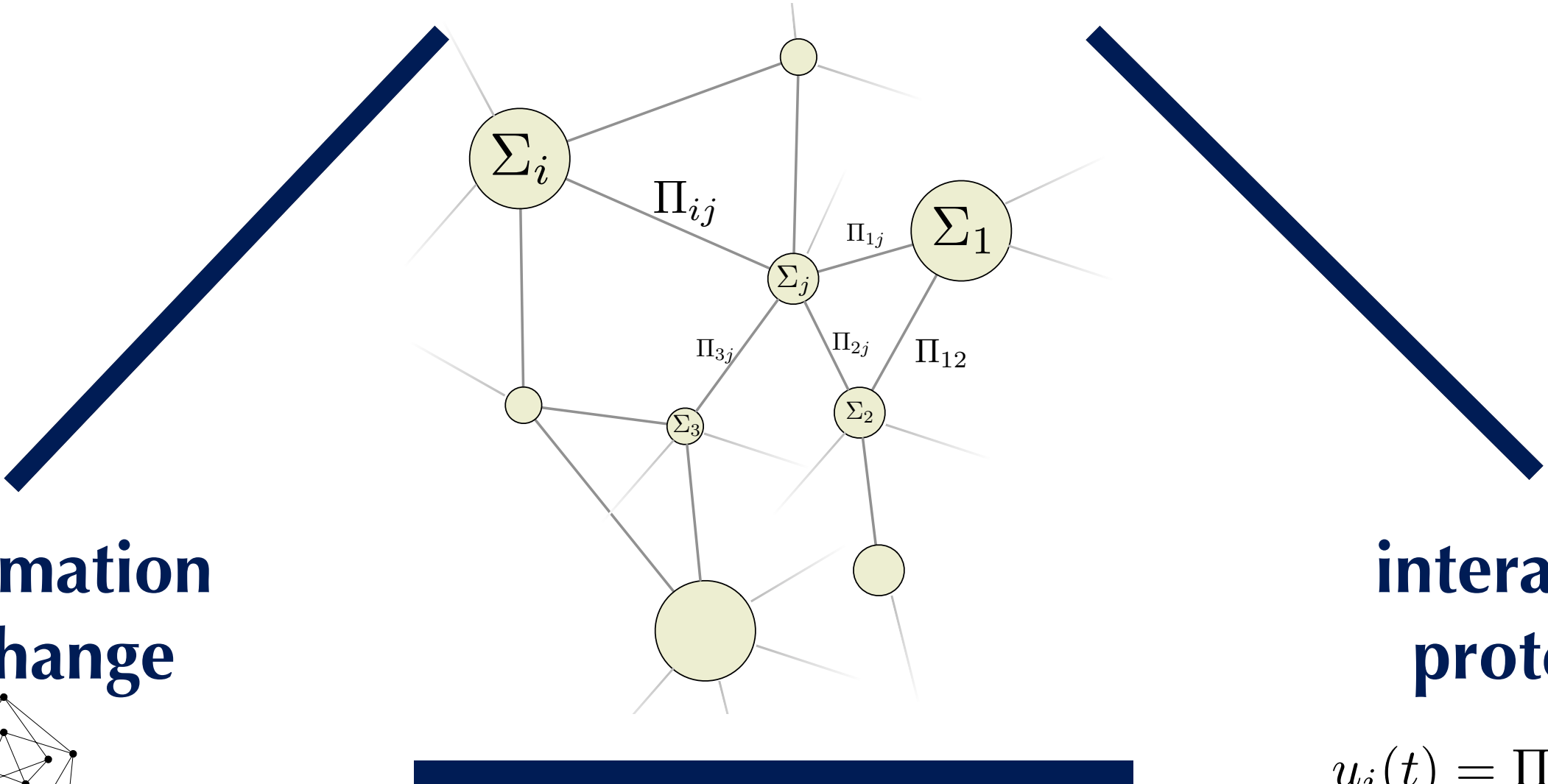
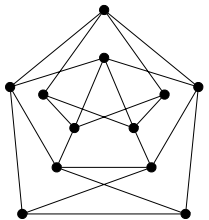


# dynamics

$$\dot{x}_i(t) = f_i(x_i(t), u_i(t))$$



information  
exchange



interaction  
protocol

$$u_i(t) = \Pi_i(x(t), \mathcal{G})$$