



**Generative Entrainment**  $D_\varphi(P_s(E_\theta(\tilde{\mathbf{x}}_t, \tilde{\mathbf{y}}_t, \tilde{\mathbf{z}}_t), \sigma_t, a, t)) \rightarrow (\dot{\tilde{\mathbf{x}}}_{t+1}, \dot{\tilde{\mathbf{y}}}_{t+1}, \dot{\tilde{\mathbf{z}}}_{t+1}, \sigma_{t+1})$

**Latent Transition Operator**  $P_s(x', y', z', \sigma' | x, y, z, \sigma, t, a) = \lambda_P(P_x, P_y, P_z, P_\sigma, f)$

**Factorized Prediction Operator**  $J_s(x', y', z', \sigma', t + \tau_\pi | x, y, z, \sigma, t, \pi) = \lambda_J(\eta_\pi, \omega_y, \omega_z, \omega_\sigma) = \mathcal{L}(P_s) ?$

**Policy**  $\mu(x, y, z, \sigma, t) = \mathcal{F}(\mathfrak{V}, J_s) ?$