```
object
aml robot.box2d.push
     world.PushWorld
   init ()
+ step()
+ draw()
+ handle event()
+ get screen point2()
+ get_point()
+ get screen point()
+ reset box()
+ get box state()
+ get_vertices()
+ generate random push()
+ to vec()
+ save_screen()
+ add_sample()
+ update()
+ apply_push()
```

+ save samples()