```
object
 aml rl envs.aml rl
     robot.AMLRIRobot
     init
           ()
+ simple_step()
+ set_base_pose()
+ set_ctrl_mode()
+ set_friction_properties()
+ enable_force_torque
 _sensors()
+ get movable joints()
+ apply_ctrl()
+ get_ik()
 + get inv dyn()
 + get_int_state()
  aml_rl_envs.aml_rl
     hand.AMLRIHand
  + __init_
            ()
  + setup_hand()
  + set fin joint state()
  + apply_action()
  + inv_kin()
  + get_finger_limits()
  + get_ee_states()
+ get_jnt_states()
  + get mass matrix()
  + convert_fin_jnt_poss
  _to_list()
  + get_jacobians()
  + get_finger_jacobian()
  + get_hand_jacobian()
aml_rl_envs.pisa_hand.pisa
      hand.PisaHand
    init
          ()
+ reset()
```