```
object
aml_robot.bullet.bullet
     robot.BulletRobot
+ secs
+ nsecs
     init
         ()
+ configure default pos()
+ configure camera()
+ get image()
+ enable force torque
 sensors()
+ disable force torque
sensors()
+ get joint details()
+ get state()
+ get_ee_velocity()
+ get ee velocity from
 bullet()
+ get_base_vel()
+ get time in seconds()
+ get movable joints()
+ get_ee_pose()
+ get link pose()
+ get link velocity()
+ get_base_pos_ori()
+ get contact points()
+ set default pos ori()
+ set pos ori()
+ get int state()
+ set int state()
+ move_using_pos_control()
+ apply_external_force()
+ apply external torque()
+ set_joint_velocities()
+ set_joint_torques()
+ get inertia matrix()
aml playground.push
 box.push_worlds.bullet.push
       world.BoxObject
    init
```

+ get\_effect()