```
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_int_poss
  _to_list()
 + get_jacobians()
 + get_finger_jacobian()
 + get_hand_jacobian()
aml_rl_envs.dlr_hand.dlr
     hand.DLRHand
     init
          ()
+ reset()
```