```
OmniState
    position
    + velocity
    + inp vel1
    + inp vel2
    + inp_vel3
    + out vel1
    + out vel2
    + out vel3
    + pos_hist1
    + pos hist2
    + rot
    + joints
    + force
    + thetas
    + buttons
    + buttons prev
    + lock
    + lock pos
    + rot
    + close_gripper
    + units ratio
             +state
     PhantomROS
+ pose publisher
+ joint_pub
+ button publisher
+ haptic_sub
+ omni name
+ sensable frame name
+ link names
+ br
+ state publisher
+ joint_publisher
+ ref frame
+ units
+ init()
+ force callback()
+ publish_omni_state()
+ init()
+ force callback()
```

+ publish omni state()