



- ① User interface sends message like go-up, stop, go-down via socket to the server, The server sends current_pos() to user.int.
- ② The server sends via pipe the message received by sockets, receives status
- ③ the Handler sends periodically via pipe messages like '+', '-' to signal the hoist to go up or down; Handler also checks extrema and stop in that case

Why using this extra process?

It allows for a more robust system in case of crash.

- If the Handler crashes the hoist stops, since it won't receive any new message with either '+' or '-'.
- If the server crashes the Handler will stop after reaching one of the extrema.

Ultimately, this accomplish the same level of security the system would have by doing the extrema check inside the hoist process, but in this way we can make it as lightweight as it can be, simulating a xenero where the Hoist process is almost at machine level while the Handler is akin to a driver.