

TRADEMARK ASSIGNMENT COVER SHEET

Electronic Version v1.1
Stylesheet Version v1.2

ETAS ID: TM423675

| | | | |
|---|---------------------------------------|------------------------|--------------------|
| SUBMISSION TYPE: | NEW ASSIGNMENT | | |
| NATURE OF CONVEYANCE: | RELEASE OF SECURITY INTEREST | | |
| CONVEYING PARTY DATA | | | |
| Name | Formerly | Execution Date | Entity Type |
| Hercules Capital, Inc. | | 03/31/2017 | Corporation: |
| RECEIVING PARTY DATA | | | |
| Name: | Persimmon Technologies Corporation | | |
| Street Address: | 200 Harvard Mill Square | | |
| City: | Wakefield | | |
| State/Country: | MASSACHUSETTS | | |
| Postal Code: | 01880 | | |
| Entity Type: | Corporation: DELAWARE | | |
| PROPERTY NUMBERS Total: 1 | | | |
| Property Type | Number | Word Mark | |
| Serial Number: | 76710009 | PERSIMMON TECHNOLOGIES | |
| CORRESPONDENCE DATA | | | |
| Fax Number: | 6034336372 | | |
| <i>Correspondence will be sent to the e-mail address first; if that is unsuccessful, it will be sent using a fax number, if provided; if that is unsuccessful, it will be sent via US Mail.</i> | | | |
| Phone: | 603-373-2079 | | |
| Email: | cbaxter@pierceatwood.com | | |
| Correspondent Name: | Christopher A. Baxter / Pierce Atwood | | |
| Address Line 1: | One New Hampshire Avenue | | |
| Address Line 2: | Suite 350 | | |
| Address Line 4: | Portsmouth, NEW HAMPSHIRE 03801 | | |
| NAME OF SUBMITTER: | Christopher A. Baxter | | |
| SIGNATURE: | /Christopher A. Baxter/ | | |
| DATE SIGNED: | 04/13/2017 | | |
| Total Attachments: 14 | | | |
| source=W6082646#page1.tif | | | |
| source=W6082646#page2.tif | | | |
| source=W6082646#page3.tif | | | |
| source=W6082646#page4.tif | | | |
| source=W6082646#page5.tif | | | |

CH \$40.00 76710009

source=W6082646#page6.tif
source=W6082646#page7.tif
source=W6082646#page8.tif
source=W6082646#page9.tif
source=W6082646#page10.tif
source=W6082646#page11.tif
source=W6082646#page12.tif
source=W6082646#page13.tif
source=W6082646#page14.tif

**TERMINATION AND RELEASE
OF SECURITY INTEREST IN INTELLECTUAL PROPERTY**

TERMINATION AND RELEASE OF SECURITY INTEREST IN INTELLECTUAL PROPERTY (“Release”), dated as of March 31, 2017 by Hercules Capital, Inc. (f/k/a Hercules Technology Growth Capital, Inc.), a Maryland corporation, as administrative agent (the “Agent”) and for the Lender (as defined in the Loan Agreement referred to below), in favor of Persimmon Technologies Corporation, a Delaware corporation (the “Released Party”).

WHEREAS, the Borrower, Agent and the Lender are parties to that certain Loan and Security Agreement, dated as of December 18, 2015, as amended by Amendment No. 1 thereto dated as of October 20, 2016 and Amendment No. 2 thereto dated as of December 21, 2016 (as amended, the “Loan Agreement”), by and among the Borrower, the Agent and the Lenders party thereto.

WHEREAS, pursuant to the terms of that certain Intellectual Property Security Agreement, dated as of December 18, 2015, by and between the Released Party and the Agent (the “Security Agreement”), the Released Party granted to the Agent a security interest in and lien on all of its Copyrights, Patents and Trademarks (as defined in the Security Agreement) together with the goodwill of the business symbolized thereby, including, without limitation, the patents and patent applications identified on Schedule A attached hereto (the “Released Patents”) and the trademark identified on Schedule B attached hereto (the “Released Trademark”); and

WHEREAS, the Agent wishes to release the security interest in and lien on the all of the Copyrights, Patents and Trademarks, including, without limitation, the Released Patents and the Released Trademark (the “Released Collateral”).

NOW, THEREFORE, for good and valuable consideration, the receipt and sufficiency of which are hereby acknowledged, the Agent states as follows:

The Agent hereby terminates and releases its security interest in and first priority lien on the Released Collateral, and the Agent hereby assigns and transfers to the Released Party, without recourse, all of its right, title and interest in and to the Released Collateral together with the goodwill of the business symbolized thereby, including, without limitation, each of the Released Patents and the Released Trademark, effective as of the date set forth above.


The Agent understands and agrees that this Release may be recorded by or for the Released Party with the United States Patent and Trademark Office or any similar office or agency within or outside the United States.

[Remainder of Page Intentionally Left Blank]

IN WITNESS WHEREOF, the Agent has executed this Release, to take effect as of the date set forth above.

AGENT:

HERCULES CAPITAL, INC.
as Agent

By: 
Name: Zhuo Huang
Title: Associate General Counsel

SCHEDULE A
to
TERMINATION AND RELEASE OF
SECURITY INTEREST IN INTELLECTUAL PROPERTY

Patents and Patent Applications

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (<i>PUB'S IN ITALICS</i>) | DATE FILED (ACTION DATE) |
|---|---|---|--|--|
| PERS- 101 PR (US) PERS-101J (US) [SMM/U] SYSTEM FOR MAKING MATERIAL PRODUCT HFT- PROCESS | 001 (016, 017)/ MOTORS 1 | SYSTEM & METHOD FOR MAKING A STRUCTURED MAGNETIC MATERIAL WITH INTEGRATED PARTICLE INSULATION (SPRAY SYSTEM WITH REACTIVE GAS) | 61/571,551 13/507,448 <i>US2013/0000447A1</i> FF in PERS 121, 122 | 06/30/2011 06/29/2012 01/03/2013 |
| PERS- 102 PR (US) PERS-102J (US) PERS-102T (PCT) [MC/U] STRATEGIC ROBOTS-CTLS | 002/ ROBOTS 2 | SYSTEM & METHOD FOR POSITION SENSING (INDUCTIVE POSITION ENCODER) | 61/573,279 13/599,930 PCT/US2012/0003 76 <i>US2013/0057263A</i> 1 <i>WO2013/032525A</i> 1 US Pat#9,222,804 No PCT exit 12/19/2 013 | 09/02/2011 08/30/2012 08/31/2012 03/07/2013 03/07/2013 12/24/2013 |
| PERS-103PR | 003 (+GOTO 020) | VACUUM- COMPATIBLE DIRECT- DRIVE SYSTEM | (61/627,030) Combined w/020 | 09/16/2011 (+GOTO 020) |
| PERS- 104 PR (US) PERS-104J (US) PERS-104T (PCT) [MC/U] PRODUCT ROADMAP ROBOT- CTLS | 005/ ROBOTS 3 | METHOD FOR TRANSPORTING A SUBSTRATE WITH A SUBSTRATE SUPPORT (ROBOT TRAJECTORY GENERATION) | 61/573,850 13/614,007 PCT/US2012/0003 95 <i>US2013/0064637A</i> 1 <i>WO2013/039550A</i> 1 US Pat#8,874,258 No PCT exit 12/19/2 013 | 09/13/2011 09/13/2012 09/13/2012 03/14/2013 03/21/2013 10/28/2014 |
| PERS- 105 PR (US) PERS-105J (US) [VR/U] STRATEGIC ROBOT-LIN | 006-007/ ROBOTS 4 | WAFER TRANSPORT SYSTEM (CONTACTLES S LINEAR DRIVE | 61/627,0 31 (61/627,0 65) 13/573,4 75 | 09/16/2011 09/16/2011 09/17/2012 04/04/2013 |

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN <i>ITALICS</i>) | DATE FILED (ACTION DATE) |
|--|---|--|--|--|
| | | SYSTEM) | <i>US2013/0085002A1</i> NO FF | |
| PERS- 107 PR (US) PERS-107J (US) [VR/U] STRATEGIC ROBOT-LIN | 008-011/ ROBOTS 5 | WAFER TRANSPORT SYSTEM (MAGNETICAL LY LEVITATED SYSTEM) | 61/627,0 65 (61/627,0 31) 13/621,3 53 <i>US2013/0071208</i> <i>A1 US</i> <i>Pat#9,927,739</i> NO FF | 09/16/2011 (09/16/2011) 09/17/2012 <i>03/21/2013</i> <i>05/12/2015</i> |
| PERS- 108 PR (US) PERS-108J (US) PERS-108T (PCT) [MC/U] | 012/ ROBOTS 6 | SYSTEM & METHOD FOR OPERATION OF A ROBOT (EFEM WITH | 61/627,067 13/614,133 PCT/US2012/00039 6 <i>US2013/0073092A1</i> | 09/15/2011 09/13/2012 09/13/2012 <i>03/21/2013</i> |
| STRATEGI C ROBOT- CTLS | | TRANSPA RENT DISPLAY) | <i>WO2013/039551A1</i> <i>US Pat#9,037,297</i> No PCT exit 12/19/2 013 | <i>03/21/2013</i> <i>05/19/2015</i> |
| PERS-109PR | 004 (+GOTO 021) | VACUUM- COMPATIBLE ROBOT ARM SYSTEM | (61/627,052) Combined w/021 | 09/16/2011 (+GOTO 021) |
| PERS- 111 PR (US) PERS-111J (US) [VR/U] STRATEGIC ROBOT- RADIAL | 013/ ROBOTS 7 | ROBOT SYSTEM WITH INDEPENDENT ARMS (ROBOT WITH INDEPENDENT ARMS AND Z DRIVES) | 61/628,825 13/670,004 <i>US2013/01217</i> <i>98 US</i> <i>Pat#9,202,733</i> NO FF | 11/07/2011 11/06/2012 <i>05/16/2013</i> <i>12/01/2015</i> |
| PERS- 113 J (US) [SMM/U] ALTERNATIVE SYSTEM FOR MAKING MATERIAL PRODUCT ROADMAP HFT- PROCESS | 001 (016, 017)/ MOTORS 8 | SYSTEM & METHOD FOR MAKING A STRUCTURED MAGNETIC MATERIAL VIA LAYERED PARTICLE DEPOSITION (SPRAY SYSTEM WITH LAYERED PARTICLES AND INSULATION) | 13/507,447 <i>US2013/0000860</i> <i>A1 US</i> <i>Pat#9,364,895</i> FF in PERS 121, 122 | 06/29/2012 <i>01/03/2013</i> <i>06/14/2016</i> |
| PERS- 124 PR (US) PERS-124J (US) [EMT/U/iEdison] NSF PI No. 1113202 PRODUCT HFT-MOTOR | 018/ MOTORS 9 | HYBRID FIELD ELECTRIC MOTOR (HYBRID RAIDAL AXIAL FLUX MOTOR) | 61/668,695 13/799,449 <i>US2014/0009025</i> NO FF (03/27/2013) | 07/06/2012 03/13/2013 <i>01/09/2014</i> |
| PERS-115J (US) | 033 | "PERSIMMON AND DESIGN" ITU TRADEMARK | 76/710,009 <i>REG No. 4,309,284</i> | 09/15/2011 |

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN <i>ITALICS</i>) | DATE FILED (ACTION DATE) |
|---|---|---|---|--|
| PERS- 116 PR (US) PERS-116J (US) [VR/U] STRATEGIC ROBOT-ARM | 014/ ROBOTS 10 | VACUUM ROBOT ADAPTED TO GRIP & TRANSPORT A SUBSTRATE & METHOD THEREOF (LOW POWER EDGE GRIP) | 61/629,830 13/688,635 <i>US2013/0294877</i> <i>A1 US</i> <i>Pub#9,401,296</i> NO FF | 11/29/2011 11/29/2012 11/17/2013 07/26/2016 |
| PERS- 117 PR (US) PERS-117J (US) PERS- 134 J (US DIV) [VR/U] PRODUCT ROBOT- ARM | 015/ ROBOTS 11 | HIGH CAPACITY ROBOT ARM (HIGH CAPACITY WRIST) | 61/668,661 13/795,736 14/940,192 <i>US2014/0007731</i> <i>US2016/0006786</i> 9 NO FF (03/27/2013) | 07/06/2012 03/12/2013 11/13/2015 01/09/2014 03/10/2016 |
| PERS- 118 J (US) [SMM/U] | 001 (016, 017)/ MOTORS | SYSTEM & METHOD FOR MAKING | 13/507,451 <i>US2013/0000861A1</i> | 06/29/2012 01/03/2013 |
| SYSTEM FOR MAKING MATERIAL IN PRODUCT HFT-PROCESS | 12 | STRUCTURED MAGNETIC MATERIAL FROM INSULATED PARTICLES (COMBUSTION BASED SPRAY DEPOSITION) | <i>US Pub#9,381,568</i> FF in PERS 121, 122 | 07/05/2016 |
| PERS- 119 PR (US) PERS-119J (US) [VR/U] STRATEGIC ROBOT-ARM | 019/ ROBOTS 13 | LINEAR ROBOT ARM WITH MULTIPLE END EFFECTORS (ARM WITH SHUTTLES AND SPACED PADDLES) | 61/669,812 13/796,578 <i>US2014/0017056A1</i> No FF 06/04/2013 | 07/10/2012 03/12/2013 01/16/2014 |
| PERS- 121 J (US) [SMM/U] PERS-121TW (TW) PERS-121T (PCT) PERS-121EP PERS-121K PERS- 121CH PERS-121JJ (122JJ@ITC) SYSTEM FOR MAKING MATERIAL PRODUCT HFT- PROCESS | 001 (016, 017)/ MOTORS 14 | SYSTEM & METHOD FOR MAKING A STRUCTURED MATERIAL (SPRAY DEPOSITION WITH A HEATING AND COATING DEVICE) | (61/571,5 51) 13/507,4 50 TW101123760 PCT/US2012/0003 06 <i>US2013/0004359A</i> 1 <i>WO2013/002840A</i> 1 TW201330030 12805078.8 <i>EP2727217</i> 10-2014-7002611 <i>KR20140058</i> 528 20128003267 0 <i>CN10363610</i> 1 2014- 518547 <i>JP2014- 521209</i> | (06/30/2011) 06/29/2012 06/29/2012 06/29/2012 01/03/2013 01/03/2013 06/29/2012 05/17/2014 06/29/2012 05/14/2014 06/29/2012 03/12/2014 06/29/2012 08/25/2014 |

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN <i>ITALICS</i>) | DATE FILED (ACTION DATE) |
|---|---|--|--|---|
| PERS- <u>122</u> J (US) PERS-122TW (TW) PERS-122T (PCT) [SMM/U] PRODUCT HFT-MATERIAL | 001 (016, 017)/ MOTORS 15 | STRUCTURED MAGNETIC MATERIAL HAVING DOMAINS WITH INSULATED BOUNDARIES (SMC MATERIAL ONLY) | (61/571,5 51) 13/507,4 49 <i>US2013/0002085</i> <i>A1 US Pat#</i> <i>9,295,488</i> TW101123751 <i>TW201330029</i> <i>TW Pat# 1544505</i> PCT/US2012/0003 07 <i>WO2013/002841A</i> <i>1</i> <i>(see 121 for JP,</i> <i>EP, CN, KR)</i> | (06/30/2011) 06/29/2012 <i>01/03/2013</i> <i>12/08/2015</i> 06/29/2012 07/16/2013 <i>08/01/2016</i> 06/29/2012 01/03/2013 |
| 101A. <u>0001</u> .P1 (US) 101A.0001.U1.US (US) | 021 (004)/ ROBOTS | LOW VARIABILIT Y ROBOT | (61/627,0 52) 61/678,7 21 | (9/16/2011) 08/02/2012 |
| 101A.0001.U1.WO(PCT) 101A.0001.U1.KR(KR) 101A.0001.U1.CN(CN) 101A.0001.U1.JP(JP) [VR/U] STRATEGIC ROBOT- RADIAL | 16 (SEE ALSO 055) | (ROBOT WITH JOINT BASED DRIVES) | 13/618,117 <i>US2013/0071218A</i> <i>1</i> PCT/US2012/0554 96 <i>WO2013/040401A</i> <i>1 KR2014-</i> <i>7009950 KR2014-</i> <i>0084036</i> CN201280054326 <i>1 CN103917337</i> JP2014-530870 <i>JP2014-527314</i> | 09/14/2012 <i>03/21/2013</i> 09/14/2012 <i>03/21/2013</i> 04/15/2014 <i>07/04/2014</i> 05/05/2014 <i>07092014</i> 03/12/2014 <i>10/09/2014</i> |
| 101A. <u>0002</u> .P1 (US) 101A.0002.U1.US (US) 101A.0002.U1.WO(PCT) 101A.0002.U1.KR(KR) 101A.0002.U1.CN(CN) 101A.0002.U1.JP(JP) [VR/U] STRATEGIC ROBOT- RADIAL | 020 (003)/ ROBOTS 17 | ROBOT DRIVE WITH PASSIVE ROTOR (ROBOT WITH ROTOR WITH NO COILS OR MAGNETS) | (61/627,0 30) 61/683,2 97 13/618,315 <i>US2013/0069450A</i> <i>1</i> PCT/US2012/0555 05 <i>WO2013/040406A</i> <i>1 KR2014-</i> <i>7010008 KR2014-</i> <i>84038</i> CN201280055476 <i>4 CN103930363</i> <i>Cn Pat#</i> <i>ZL201280055476</i> <i>4</i> JP2014-530872 <i>JP2014-528170</i> <i>ABANDON US</i> <i>ONLY</i> <i>06/20/2016 MH</i> <i>ABANDON JP</i> <i>10/6/16</i> | (9/16/2011) 08/15/2012 09/14/2012 <i>03/21/2013</i> 09/14/2012 <i>03/21/2013</i> 04/15/2014 <i>07/04/2014</i> 05/12/2014 <i>01/16/2014</i> <i>10/12/2016</i> 03/12/2014 <i>10/23/2014</i> |
| 101A. <u>0003</u> .P2(US) 101A.0003.U1(US) [EMT/U] | 022/ MOTORS 18 | HYBRID MOTOR (HYBRID) | 61/712,931 13/793,250 <i>US2014/0103752</i> | 10/12/2012 03/11/2013 04/17/2014 |

{W6073440.1}

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN <i>ITALICS</i>) | DATE FILED (ACTION DATE) |
|---|---|---|---|--|
| STRATEGIC HFT-MOTOR | | FLUX MOTOR WITH MAGNETS IN STATOR) | <i>US Pat#</i> 9,592,952 NO FF (08/27/2013) | 11/22/2016 |
| 101A.0002.U2.US (US) 101A.0002.U2.JP [VR/U] PRODUCT ROBOT- RADIAL | 023 (020 DIVISION)/ ROBOTS 19 | ROBOT DRIVE WITH RADIALLY ADJUSTABLE SENSOR CONNECTION (ROBOT WITH ISOLATED READ HEAD) | (61/627,0 30) 13/744,9 00 <i>US2014/0077637</i> JP2016206769 FF – See 020 Except JP Division here | (9/16/2011) 01/18/2013 03/20/2014 10/21/2016 |
| 101A.0002.U3.US (US) | 024 (020 DIVISION)/ ROBOTS | ROBOT WITH HEAT DISSIPATING STATOR (HIGH TORQUE | (61/627,0 30) 13/744,9 66 <i>US2014/007629</i> | (9/16/2011) 01/18/2013 03/20/2014 |
| 101A.0002.U3.JP [VR/U] PRODUCT ROBOT- RADIAL | 20 | VACUUM ROBOT) | <i>US Pat# 8,716,909</i> JP2016206770 FF – See 020 Except JP Division here | 05/06/2014 10/21/2016 |
| 101A.0004.P1.(US) 101A.0004.U1.(US) [VR/U] PRODUCT ROADMAP ROBOT- CTLS | 025/ ROBOTS 21 | ROBOT HAVING REPEATABLE DISTURBANCE COMPENSATION ALGORITHM (TORQUE RIPPLE COMPENSATION) | 61/727,813 13/793,665 <i>US2014/0139162</i> <i>US Pat#</i> 9,041,336 No FF (08/27/2013) | 11/19/2012 03/11/2013 05/22/2014 05/26/2015 |
| 101A.0005.P1.US (US) | 026/ROBOTS | ROBOT WITH INTELLIGENT AUXILIARY INTERFACE | 61/727,819 ABANDON (08/27/2013) | 11/19/2012 |
| 101A.0006.P1.(US) 101A.0006.U1.(US) [VR/U] STRATEGIC ROBOT- ARM | 027/ ROBOTS 22 | ROBOT WITH HIGH STIFFNESS COUPLING (STIFF SCARA ARM) | 61/727,822 13/790,156 <i>US2014/0137690</i> <i>US Pat#</i> 9,452,527 No FF (08/27/2013) | 11/19/2012 03/08/2013 05/22/2014 09/27/2016 |
| 101A.0007.P1.US (US) 101A.0007.P2.US (US) 101A.0007.U1.(US) 101A.0007.U1.(WO) 101A.0007.U1.(JP) | 029/ ROBOTS 23 | ROBOT HAVING ARM WITH UNEQUAL LINK LENGTHS (UNEQUAL LINK OVER / UNDER ARM) | 61/754,125 61/762,063 13/833,732 PCT/US2014/0114 16 <i>US2014/0205416</i> <i>WO/2014/113364</i> | 01/18/2013 02/07/2013 03/15/2013 01/14/2014 07/24/2014 07/24/2014 |

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN <i>ITALICS</i>) | DATE FILED (ACTION DATE) |
|---|---|---|--|--|
| 101A.0007.U1.(KR) 101A.0007.U1.(CN) [VR/U] PRODUCT ROBOT- ARM | | | JP 2015- 553776 <i>JP2016505219</i> KR 2015- 7022143 <i>KR201501106</i> 25 CN <i>105026115</i> <i>US Pub#</i> <i>9,149,936</i> (File JP,KR,CN 05/15/2015) | 02/18/2016 <i>02/18/2016</i> 08/17/2015 <i>10/02/2015</i> <i>08/31/2015</i> <i>10/06/2015</i> |
| 101A. <u>0008</u> .U1.(US) [VR/U] PRODUCT ROBOT- CTLS | 034/ <u>ROBOTS</u> 24 | ADAPTIVE PLACEMENT SYSTEM & METHOD (WAFER PLACEMENT CORRECTION ALGORITHM) | 13/836,020 <i>US Pub# 9,196,518</i> No FF & No Pub | 03/15/2013 <i>11/24/2015</i> |
| PERS- <u>126</u> J (US) | 035 (001CIP) <u>/MOTORS</u> | SYSTEM & METHOD FOR MAKING A STRUCTURED | 13/836,615 <i>US2013/0292081</i> PCT/US2014/02073 6 | 03/15/2013 <i>03/05/2014</i> 03/15/2013 |
| PERS-126T(PCT) [SMM/U/iEdison] NSF PI No. 1113202 PRODUCT ROADMAP HFT- PROCESS | 25 | MATERIAL WITH INTEGRATED PARTICLE INSULATION (SPRAY DEPOSITION WITH MASKS) | <i>WO/2014/149761</i> EU 14769666.0 <i>EU 2969315</i> <i>JP2016516896</i> [FILE EU, JP ONLY 08/31/2015] | <i>09/25/2014</i> <i>01/20/2016</i> <i>06/09/2016</i> |
| No File – 06/04/2013 | 036/ROBOTS | TEACH PENDANT MOVEMENT CONTROL | N/A | N/A |
| 101A. <u>0010</u> .P1.(US) 101A.0010.U1(US) 101A.0010.WO(PCT) [VR/U] PRODUCT ROADMAP ROBOT- RADIAL | 037/ <u>ROBOTS</u> 26 | ROBOT AND ADAPTIVE PLACEMENT SYSTEM AND METHOD (QUAD APS ROBOT) | 61/831,320 14/295,419 <i>US2014/0365004</i> PCT/US2014/0407 48 <i>WO/2014/197537</i> <i>US2014/0365004</i> KR2016-7000034 <i>KR20160018656</i> [EXIT TO KR ONLY 09/22/2015] | 06/05/2013 06/04/2014 <i>12/11/2016</i> 06/04/2014 <i>12/11/2014</i> <i>12/11/2014</i> 01/04/2016 <i>02/17/2016</i> |
| 101A. <u>0009</u> .P1.(US) [VR/P] | 038/ <u>ROBOTS</u> | ROBOT WITH INDEPENDENT ARMS | 61/825,162 See 059 for conver sion | 05/20/2013 |
| 101A. <u>0011</u> .P1.(US) 101A. <u>0011</u> .U1.(US) [VR/U] STRATEGIC ROBOT- RADIAL | 039/ <u>ROBOTS</u> 27 | REDUCED FOOTPRINT SUBSTRATE TRANSPORT PLATFORM (SMALL FOOTPRINT | 61/864,028 14/454,926 <i>US2015/0044001</i> (No FF 07/23/2014) | 08/09/2013 08/08/2014 <i>02/12/2015</i> |

{W6073440.1}

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN <i>ITALICS</i>) | DATE FILED (ACTION DATE) |
|--|---|---|---|--|
| | | QUAD PLATFORM) | | |
| 101A. <u>0012</u> .P1.(US) 101A.0012.U1(US) [VR/U] PRODUCT ROADMAP ROBOT- CTLS | 040/ <u>ROBOTS</u> 28 | ROBOT AND ADAPTIVE PLACEMENT SYSTEM AND METHOD (FIDUCIAL BASED APS) | 61/868,131 14/295,447 <i>US2014/0365011</i> (See 037 for FF) | 08/21/2013 06/04/2014 12/11/2014 |
| 101A. <u>0013</u> .P1(US) 101A. <u>0013</u> .U1(US) [VR/U] STRATEGIC ROBOT-LINEAR | 041/ <u>ROBOTS</u> 29 | SUBSTRATE TRANSPORT VACUUM PLATFORM (LINEAR PLATFORMS) | 61/875,275 14/480,803 <i>US2015/0071737</i> (No FF 07/23/2014) | 09/09/2013 09/09/2014 03/12/2015 |
| PERS- <u>131</u> PR (US) 101A. <u>0018</u> .U1(US) [SMM/U/iEdison] NSF PII No. 1230458 PRODUCT HFT-MATERIAL | 042/ <u>MOTORS</u> 30 | STRUCTURES UTILIZING A SOFT MAGNETIC MATERIAL AND METHODS FOR MAKING (FEAL ALLOY & STRUCTU RE) | 61/884,415 14/501,603 <i>US2015/0118407</i> (PCT exit EU & CN + see 048 for FF 01/07/2016) | 09/30/2013 09/30/2014 04/30/2015 |
| 101A. <u>0014</u> .P1.(US) 101A. <u>0014</u> .P2.(US) 101A. <u>0014</u> .U1.(US) 101A. <u>0014</u> .U1.(WO) [VR/U] PRODUCT ROBOT- RADIAL | 043/ <u>ROBOTS</u> 31 (SEE ALSO 067) | ROBOT HAVING INTERCHANGEA BILITY FEATURES (REPLACEABLE ROBOT DRIVE) | 61/937,848 61/970,533 14/617,227 <i>US2015/0228509</i> PCT/US2015/149 83 <i>WO2015120369</i> <i>US Pat# 9,478,451</i> (No PCT exit 06/08/20 16) | 02/10/2014 03/26/2014 02/09/2015 08/13/2015 02/09/2015 08/13/2015 10/25/2016 |
| 101A. <u>0015</u> .P1(US) 101A.0015.U1(US) [VR/U] PRODUCT ROADMAP ROBOT- CTLS | 044/ <u>ROBOTS</u> 32 | ROBOT AND ADAPTIVE PLACEMENT SYSTEM AND METHOD (QUAD APS ALGORITHM) | 61/945,306 14/295,466 <i>US2014/0365005</i> <i>US Pat# 9,330,951</i> (See 037 for FF) | 02/27/2014 06/04/2014 12/11/2014 05/03/2016 |
| 101A. <u>0016</u> .P1(US) 101A.0016.U1(US) 101A.0016.U1(WO) [VR/U] STRATEGIC ROBOT- RADIAL | 045/ <u>ROBOTS</u> 33 | ROBOT HAVING ISOLATED STATOR AND ENCODER (ROBOT DRIVE WITH ISOLATION) | 61/981,987 14/691,866 <i>US</i> <i>2015/0303764</i> PCT/US2015/26 752 <i>WO2015/164298</i> KR2016- 7032308 JP2016-563434 CN (File CN, KR, JP 10/06/2016) | 04/21/2014 04/21/2015 10/22/2015 04/21/2015 10/29/2015 11/18/2016 |
| 101A. <u>0017</u> .P1(US) | 046/ <u>ROBOTS</u> | 2 LINK | 61/988,559 | 05/05/2014 |

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN <i>ITALICS</i>) | DATE FILED (ACTION DATE) |
|---|---|---|--|--|
| [VR/U] PRODUCT ROBOT- ARM | 34 | ARM TRAJEC TORY (2 LINK SPECIFIC TRAJECTO RY GENERATI ON) | 14/703,216 <i>US 2015/0314459</i> (Convert US + No FF 01/29/2015) | 05/04/2015 <i>11/05/2015</i> |
| 101A. 0020 .P1(US) 101A. 0020 .U1(US) 101A. 0020 .U1(WO) [VR/U] STRATEGIC ROBOT- LINEAR | 047/ ROBOTS 35 | SUBSTRATE TRANSPORT VACUUM PLATFORM (LINEAR VACUUM PLATFORMS) | 61/929,536 14/601,455 <i>US2015/0214086</i> PCT/US2015/0121 55 <i>WO2015/112538</i> CN201580005228. 2 KR 20167022613 <i>KR20160108549</i> (No PCT exit 06/21/20 16) | 01/21/2014 01/21/2015 <i>07/30/2015</i> 01/21/2015 <i>07/30/2015</i> 07/20/2016 08/18/2016 <i>09/19/2016</i> |
| PERS- 131 .PR (US) PERS- 131 .P2 (US) PERS- 131 .P3 (US) PERS- 131 .P4 (US) 101A. 0019 .U1(US) | 048/ MOTORS 36 | STRUCTURES UTILIZING A SOFT MAGNETIC MATERIAL & METHODS FOR MAKING (HYBRID MOTOR | 61/884,415 61/920,043 61/933,386 61/941,644 14/501,668 <i>US2016/0043602</i> | 09/30/2013 12/23/2013 01/30/2014 02/19/2014 09/30/2014 <i>02/11/2016</i> |
| 101A. 0019 .U1(WO) [SMM/U/iEdison] PRODUCT HFT- MOTOR | | WITH CONICAL STATOR) | PCT/US14/058 291 <i>WO2015/04873</i> 3 JP 5160599274 CN 201480053873.7 <i>CN105829571</i> A EU 14847355.6 <i>EU3036351</i> KR2016- 7010017 <i>KR201665122</i> (PCT Exit EU, CN, JP, KR 01/07/2016) | 09/30/2014 <i>04/02/2015</i> 03/25/2016 <i>08/03/2016</i> 03/22/2016 <i>06/29/2016</i> 04/15/2016 <i>06/08/2016</i> |
| 101A. 0021 .P1(US) 101A. 0021 .U1(US) 101A. 0021 .U1(WO) [VR/U] PRODUCT ROADMAP ROBOT- CTLS | 049/ ROBOTS 37 | ROBOT ADAPTIVE PLACEMENT SYSTEM WITH END EFFECTOR POSITION ESTIMATION (APS WITH FLEXIBLE DYNAMICS) | 62/081,209 14/944,603 <i>US2016013681</i> 2 PCT/US15/061 088 <i>WO2016/08145</i> 9 | 11/18/2014 11/18/2015 <i>05/19/2016</i> 11/18/2015 <i>05/19/2016</i> (PCT Exit 05/18/2017) |

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN <i>ITALICS</i>) | DATE FILED (ACTION DATE) |
|---|---|---|--|--|
| 101A.0022.P1(US) 101A.0022.U1(US) [VR/U] PRODUCT ROBOT- ARM | 050/ <u>ROBOTS</u> 38 | HIGH CAPACITY ROBOT WITH HIGH CAPACITY WRIST (ROBOT WITH COMPOSITE WRIST) | 62/087,873 14/956,678 <i>US20160158943</i> (CONVERT US ONLY 09/22/2015) | 12/05/2014 12/02/2015 06/09/2016 |
| 101A.0023.P1(US) 101A.0023.U1(US) [SMM/U] STRATEGIC HFT-MOTOR | 051/ <u>MOTORS</u> 39 | MOTOR WITH COMPOS ITE HOUSIN G (HOUSING = STATOR MOLD) | 62/100,702 14/988,814 <i>US2016/0197523</i> (CONVERT US ONLY 09/22/2015) | 01/07/2015 01/06/2016 07/07/2016 |
| 101A.0024.P1(US) 101A.0024.U1(US) 101A.0024.U1(WO) [SMM/U/iEdison] NSF PII No. 1230458 PRODUCT ROADMAP HFT- MOTOR | 052/ <u>MOTORS</u> 40 | MOTOR HAVING NON CIRCULAR STATOR (NON CIRCULAR Z AXIS MOTOR) | 62/110,752 15/011,802 <i>US20160226321</i> PCT/US2016/0160 55 <i>WO2016126633</i> (Convert US & file PCT 01/07/2016) | 02/02/2015 02/01/2016 08/04/2016 02/02/2016 08/11/2016 (PCT Exit 08/02/2017) |
| 101A.0025.P1(US) 101A.0025.U1(US) 101A.0025.U1(WO) [VR/U] PRODUCT ROADMAP ROBOT- LINEAR | 053/ <u>ROBOTS</u> 41 | MOVEABLE POWER COUPLING AND ROBOT WITH MOVEABLE POWER COUPLING (NON- CONTACT POWER COUPLING) | 62/112,768 15/017,941 <i>US20160229296</i> PCT/US2016/0169 33 <i>WO2016127152</i> (Convert US & file PCT 01/07/2016) | 02/06/2015 02/08/2016 08/11/2016 02/08/2016 08/11/2016 (PCT EXIT 08/06/2017) |
| 101A.0026.P1(US) 101A.0026.U1(US) | 054/ <u>ROBOTS</u> | DUAL ARM ROBOT WITH STACKED SIDE | 62/112,820 15/017,970 | 02/06/2015 02/08/2016 |
| 101A.0026.U1(WO) [VR/U] PRODUCT ROADMAP ROBOT- ARM | 42 (029 CIP) | BY SIDE END EFFECTOR CONFIGURATI ONS (DUAL ARM ROBOT) | <i>US20160167229</i> PCT/US2016/0169 46 <i>WO2016127160</i> (Convert US & file PCT 01/07/2016) | 06/16/2016 02/08/2016 08/11/2016 (PCT EXIT 08/06/2017) |
| 101A.0027.P1(US) 101A.0027.U1(US) 101A.0027.U1(WO) [VR/U] PRODUCT ROBOT- ARM | 055/ <u>ROBOTS</u> 43 | TWO DEGREE OF FREEDOM 3 LINK ROBOT ARM MECHANISMS (SINGLE EE ROBOT) | 62/132,006 15/067,689 <i>US20160263742</i> PCT/US2016/0219 99 <i>WO2016145305</i> (Combine 055&056, Convert US & file PCT 01/07/2016) | 03/12/2015 03/11/2016 09/15/2016 03/11/2016 09/15/2016 (PCT EXIT 09/12/2017) |
| 101A.0028.P1(US) 101A.0028.P2(US) | 056/ <u>ROBOTS</u> | ROBOT ARM MECHANISMS | 62/135,490 62/137,458 | 03/19/2015 03/24/2015 |

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN <i>ITALICS</i>) | DATE FILED (ACTION DATE) |
|--|---|---|---|---|
| 101A.0028.P3(US) 101A.0028.P4(US) [VR/P] | | WITH 2 END EFFECTORS (DUAL EE ROBOT) | 62/264,436 62/275,884 (Combined 055&056, See 055 for FF) | 12/08/2015 01/07/2016 |
| PERS 133J(US) [VR/U] STRATEGIC ROBOT- LINEAR | 057/ <u>ROBOTS</u> 44 | WAFER TRANSPORT SYSTEM (LINEAR SCREW 133J DIVISION) | 14/708,644 <i>US 2015/0243539</i> <i>US Pat# 9,202,735</i> | 05/11/2015 08/27/2015 12/01/2015 |
| 101A.0029.P1(US) [VR/P] PRODUCT ROADMAP ROBOT- ARM | 058/ <u>ROBOTS</u> 45 | UNEQUAL LINK LENGTH ARM WITH VARIABLE NON LINEAR WRIST ORIENTATION (NON LINEAR UNEQUAL LINK LENGTH ROBOT) | 62/193,293 15/212,441 (Convert US only 06/08/2016) | 07/16/2015 07/18/2016 |
| 101A.0007.U2(US) [VR/U] PRODUCT ROBOT- ARM | 059/ <u>ROBOTS</u> 46 | ROBOT HAVING ARM WITH UNEQUAL LINK LENGTHS (UNEQUAL LINK LENGTH IC 0007 DIV) | 14/761,718 <i>US2015/0352714</i> | 07/07/2015 12/10/2015 |
| 101A.0001.U2(US) 101A.0001.U2(JP) [VR/U] PRODUCT ROADMAP ROBOT- RADIAL | 060/ <u>ROBOTS</u> 47 (021U2 DIV) | LOW VARIABILIT Y ROBOT (7 AXIS ROBOT) | 14/938,292 <i>US20160064263</i> JP2014530870 | 11/11/2015 03/03/2016 10/28/2016 |
| 101A.0037.P1(US) 101A.0037.P2(US) 101A.0037.U1(US) [VR/P] STRATEGI C HFT- OTHER | 061/ <u>MOTORS</u> 48 | ELECTRIC BRAKE CALIPER (SELF CONTAINED CALIPER) | 62/200,826 62/218,633 15/228,501 (Convert US only no FF 07/15/2016) | 08/04/2015 09/15/2015 08/04/2016 |
| 101A.0007.U3(US) [VR/U] PRODUCT ROBOT- ARM | 062/ <u>ROBOTS</u> 49 | ROBOT HAVING ARM WITH UNEQUAL LINK LENGTHS (BROAD UNEQUAL LINK LENGTH ROBOT 0007 CONT) | 14/827,506 <i>US2015/0352729</i> | 08/17/2015 12/10/2105 |
| 101A.0039.P1(US) [VR/P] STRATEGIC ROBOT-LINEAR | 063/ <u>ROBOTS</u> 50 | MATERIAL HANDLING SYSTEM | 62/280,788 | 01/20/2016 (FF/C 01/20/2017) |
| 101A.0040.P1(US) [VR/P] PRODUCT ROADMAP ROBOT- | 064/ <u>ROBOTS</u> 51 | ROBOT DRIVE WITH ISOLATED OPTICAL | 62/310,989 | 03/21/2016 (FF/C 03/21/2017 - 023 CIP?) |

| ATTORNEY FILE NO. [CATEGORY] | OUR NETWORK FILE NO./CLASS (COUNT # = LG. TYPE) | TITLE | SERIAL NO. (PUB'S IN ITALICS) | DATE FILED (ACTION DATE) |
|--|---|---|-------------------------------------|---|
| RADIAL | | ENCODER | | |
| 101A.0041.P1(US) [SMM/P] PRODUCT ROADMAP HFT- MATERIAL | 065/ <u>MOTORS</u> 52 | MATERIAL WITH DIRECTIONAL MICROSTRUC TURE | 62/320,723 | 04/11/2016 (FF/C 04/11/2017) |
| 101A.0042.P1(US) 101A.0042.P2(US) [VR/P] PRODUCT ROADMAP ROBOT ARM | 066/ <u>ROBOTS</u> 53 | ROBOT MANIPULATOR WITH SUPPLEMENTAL DAMPING | 62/320,775 62/340,638 | 04/11/2016 05/24/2016 (FF/C 04/11/2017) |
| 101A.0014.U2(US) [VR/P] PRODUCT ROADMAP ROBOT ARM | 067/ <u>ROBOTS</u> 54 (043 DIVISION) | TWO DEGREE OF FREEDOM 3 LINK ROBOT ARM MECHANIS MS | 15/266,562 | 09/15/2016 |
| 101A.0001.U3(US) [VR/P] PRODUCT ROADMAP ROBOT- LINEAR | 068/ <u>ROBOTS</u> 55 (021U3 DIV) | LOW VARIABILIT Y LINEAR ROBOT (FIGURES 19- 22) | 15/294,099 | 09/14/2016 |
| 101A.0043.P1(US) | 069/ROBOTS | MATERIAL- HANDLING ROBOT WITH MULTIPLE END- EFFECTORS | 62/459,135 | 02/15/2017 |

SCHEDULE B
to
TERMINATION AND RELEASE OF
SECURITY INTEREST IN INTELLECTUAL PROPERTY
Trademark

| Word Mark | Mark Drawing Code | Serial Number | Registration Number | Registration Date |
|---------------------------|--|----------------------|----------------------------|--------------------------|
| PERSIMMON TECHNOLOGIES | (3) DESIGN PLUS WORDS, LETTERS, AND/OR NUMBERS | 7671009 | 4309284 | March 26, 2013 |