

APPLICANT: Sony Ericsson Mobile Communications Inc.

FCC ID: **PY7A1061011**



Sony Ericsson

REPORT

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Prepared (also subject responsible if other) SEM/CV/PF/P Gerard Hayes	No. REP 2005 004 T292A 01
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Appendix 4

Probe Calibration Certificates



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ET3DV6 SN:1586

May 26, 2005

DASY - Parameters of Probe: ET3DV6 SN:1586

Sensitivity in Free Space^A

Diode Compression^B

NormX	1.90 ± 10.1%	μV/(V/m) ²	DCP X	94 mV
NormY	1.84 ± 10.1%	μV/(V/m) ²	DCP Y	94 mV
NormZ	1.89 ± 10.1%	μV/(V/m) ²	DCP Z	94 mV

Sensitivity in Tissue Simulating Liquid (Conversion Factors)

Please see Page 8.

Boundary Effect

TSL 900 MHz Typical SAR gradient: 5 % per mm

Sensor Center to Phantom Surface Distance		3.7 mm	4.7 mm
SAR _{tsa} [%]	Without Correction Algorithm	8.4	4.3
SAR _{tsa} [%]	With Correction Algorithm	0.1	0.2

TSL 1750 MHz Typical SAR gradient: 10 % per mm

Sensor Center to Phantom Surface Distance		3.7 mm	4.7 mm
SAR _{tsa} [%]	Without Correction Algorithm	12.2	8.2
SAR _{tsa} [%]	With Correction Algorithm	0.8	0.1

Sensor Offset

Probe Tip to Sensor Center 2.7 mm

The reported uncertainty of measurement is stated as the standard uncertainty of measurement multiplied by the coverage factor k=2, which for a normal distribution corresponds to a coverage probability of approximately 95%.

^A The uncertainties of NormX,Y,Z do not affect the E²-field uncertainty inside TSL (see Page 8).

^B Numerical linearization parameter: uncertainty not required.

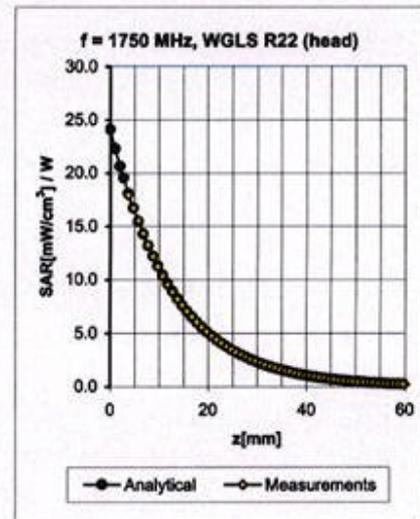
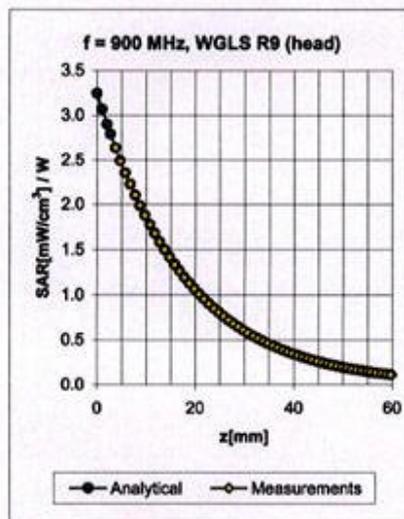


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Conversion Factor Assessment



f [MHz]	Validity [MHz] ^c	TSL	Permittivity	Conductivity	Alpha	Depth	ConvF Uncertainty
835	± 50 / ± 100	Head	41.5 ± 5%	0.90 ± 5%	0.62	1.76	6.58 ± 11.0% (k=2)
900	± 50 / ± 100	Head	41.5 ± 5%	0.97 ± 5%	0.61	1.78	6.46 ± 11.0% (k=2)
1750	± 50 / ± 100	Head	40.1 ± 5%	1.37 ± 5%	0.59	2.28	5.29 ± 11.0% (k=2)
1900	± 50 / ± 100	Head	40.0 ± 5%	1.40 ± 5%	0.56	2.50	5.10 ± 11.0% (k=2)
2450	± 50 / ± 100	Head	39.2 ± 5%	1.80 ± 5%	0.66	2.22	4.58 ± 11.8% (k=2)
835	± 50 / ± 100	Body	55.2 ± 5%	0.97 ± 5%	0.54	1.96	6.51 ± 11.0% (k=2)
900	± 50 / ± 100	Body	55.0 ± 5%	1.05 ± 5%	0.52	2.05	6.21 ± 11.0% (k=2)
1750	± 50 / ± 100	Body	53.4 ± 5%	1.49 ± 5%	0.55	2.76	4.71 ± 11.0% (k=2)
1900	± 50 / ± 100	Body	53.3 ± 5%	1.52 ± 5%	0.56	2.76	4.61 ± 11.0% (k=2)
2450	± 50 / ± 100	Body	52.7 ± 5%	1.95 ± 5%	0.68	2.13	4.26 ± 11.8% (k=2)

^c The validity of ± 100 MHz only applies for DASY v4.4 and higher (see Page 2). The uncertainty is the RSS of the ConvF uncertainty at calibration frequency and the uncertainty for the indicated frequency band.



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DASY - Parameters of Probe: ET3DV6 SN:1587

Sensitivity in Free Space^A

Diode Compression^B

NormX	2.05 ± 10.1%	μV/(V/m) ²	DCP X	95 mV
NormY	1.92 ± 10.1%	μV/(V/m) ²	DCP Y	95 mV
NormZ	1.79 ± 10.1%	μV/(V/m) ²	DCP Z	95 mV

Sensitivity in Tissue Simulating Liquid (Conversion Factors)

Please see Page 8.

Boundary Effect

TSL 900 MHz Typical SAR gradient: 5 % per mm

Sensor Center to Phantom Surface Distance		3.7 mm	4.7 mm
SAR _{90%} [%]	Without Correction Algorithm	8.1	4.4
SAR _{90%} [%]	With Correction Algorithm	0.1	0.2

TSL 1750 MHz Typical SAR gradient: 10 % per mm

Sensor Center to Phantom Surface Distance		3.7 mm	4.7 mm
SAR _{90%} [%]	Without Correction Algorithm	12.4	8.5
SAR _{90%} [%]	With Correction Algorithm	0.5	0.1

Sensor Offset

Probe Tip to Sensor Center 2.7 mm

The reported uncertainty of measurement is stated as the standard uncertainty of measurement multiplied by the coverage factor k=2, which for a normal distribution corresponds to a coverage probability of approximately 95%.

^A The uncertainties of NormX,Y,Z do not affect the E²-field uncertainty inside TSL (see Page 8).

^B Numerical linearization parameter; uncertainty not required.

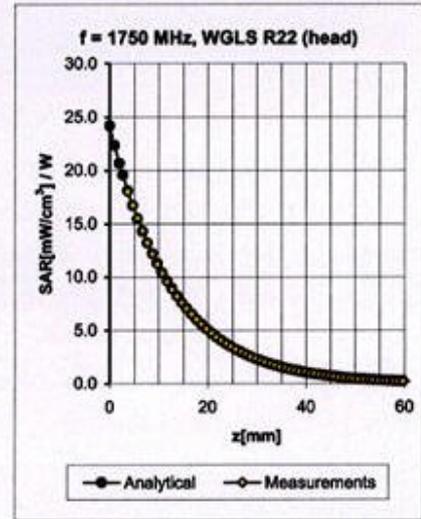
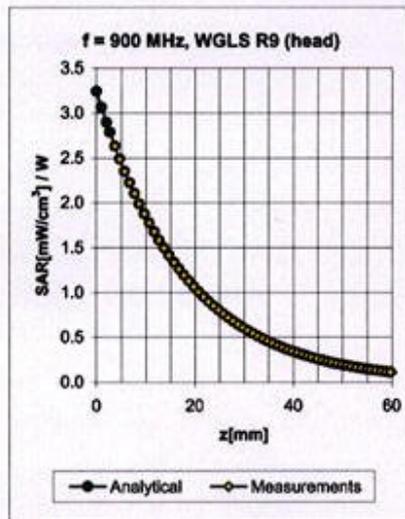


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f [MHz]	Validity [MHz] ^c	TSL	Permittivity	Conductivity	Alpha	Depth	ConvF Uncertainty
835	± 50 / ± 100	Head	41.5 ± 5%	0.90 ± 5%	0.60	1.76	6.78 ± 11.0% (k=2)
900	± 50 / ± 100	Head	41.5 ± 5%	0.97 ± 5%	0.55	1.85	6.50 ± 11.0% (k=2)
1750	± 50 / ± 100	Head	40.1 ± 5%	1.37 ± 5%	0.50	2.53	5.45 ± 11.0% (k=2)
1900	± 50 / ± 100	Head	40.0 ± 5%	1.40 ± 5%	0.47	2.71	5.05 ± 11.0% (k=2)
2450	± 50 / ± 100	Head	39.2 ± 5%	1.80 ± 5%	0.58	2.40	4.55 ± 11.8% (k=2)
835	± 50 / ± 100	Body	55.2 ± 5%	0.97 ± 5%	0.51	1.97	6.65 ± 11.0% (k=2)
900	± 50 / ± 100	Body	55.0 ± 5%	1.05 ± 5%	0.51	2.03	6.37 ± 11.0% (k=2)
1750	± 50 / ± 100	Body	53.4 ± 5%	1.49 ± 5%	0.48	2.94	4.74 ± 11.0% (k=2)
1900	± 50 / ± 100	Body	53.3 ± 5%	1.52 ± 5%	0.50	3.13	4.57 ± 11.0% (k=2)
2450	± 50 / ± 100	Body	52.7 ± 5%	1.95 ± 5%	0.53	2.51	4.16 ± 11.8% (k=2)

^c The validity of ± 100 MHz only applies for DASY v4.4 and higher (see Page 2). The uncertainty is the RSS of the ConvF uncertainty at calibration frequency and the uncertainty for the indicated frequency band.

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Appendix 5

Measurement Uncertainty Budget



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Table 1a. Uncertainty Budget for System Performance Check (Dipole & flat phantom) DASY3 System

a	b	c	d	e = f(d,k)	f	g	h = c x f / e	i = c x g / e	k
Uncertainty Component	Sec.	Tol. (± %)	Prob. Dist.	Div.	c _i (1-g)	c _i (10-g)	1-g u _i (±%)	10-g u _i (±%)	v _i
Measurement System									
Probe Calibration (k=1)	E.2.1	4.8	N	1	1	1	4.8	4.8	∞
Axial Isotropy	E.2.2	4.7	R	1.73	0.707	0.707	1.9	1.9	∞
Hemispherical Isotropy	E.2.2	9.6	R	1.73	0.707	0.707	3.9	3.9	∞
Boundary Effect	E.2.3	8.3	R	1.73	1	1	4.8	4.8	∞
Linearity	E.2.4	4.7	R	1.73	1	1	2.7	2.7	∞
System Detection Limits	E.2.5	1.0	R	1.73	1	1	0.6	0.6	∞
Readout Electronics	E.2.6	1.0	N	1	1	1	1.0	1.0	∞
Response Time	E.2.7	0.0	R	1.73	1	1	0.0	0.0	∞
Integration Time	E.2.8	0.0	R	1.73	1	1	0.0	0.0	∞
RF Ambient Conditions	E.6.1	3.0	R	1.73	1	1	1.7	1.7	∞
Probe Positioner Mechanical Tolerance (corresponds to the mechanical constrains of the robot)	E.6.2	0.4	R	1.73	1	1	0.2	0.2	∞
Probe Positioning with respect to Phantom Shell	E.6.3	2.9	R	1.73	1	1	1.7	1.7	∞
Extrapolation, interpolation and Integration Algorithms for Max. SAR Evaluation	E.5	3.9	R	1.73	1	1	2.3	2.3	∞
Dipole									
Dipole Axis to Liquid Distance	8, E.4.2	1.0	R	1.73	1	1	0.6	0.6	∞
Input Power and SAR Drift Measurement	8, 6.6.2	5.0	R	1.73	1	1	2.9	2.9	∞
Phantom and Tissue Parameters									
Phantom Uncertainty - shell thickness tolerance	E.3.1	4.0	R	1.73	1	1	2.3	2.3	∞
Liquid Conductivity - deviation	E.3.2	4.3	R	1.73	0.64	0.43	1.59	1.07	∞



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from target values (5)									
Liquid Conductivity - measurement uncertainty (6)	E.3.3	6.20	R	1.73	0.64	0.43	2.29	1.54	∞
Liquid Permittivity - deviation from target values (5)	E.3.2	3.7	R	1.73	0.6	0.49	1.28	1.05	∞
Liquid Permittivity - measurement uncertainty (6)	E.3.3	6.08	R	1.73	0.6	0.49	2.11	1.72	∞
Combined Standard Uncertainty			RSS				10.61	10.31	
Expanded Uncertainty (95% C.L.)							21.22	20.62	



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Table 1b. Uncertainty Budget for System Performance Check (Dipole & flat phantom) DASY4 System

a	b	c	d	e = f(d,k)	f	g	h = c x f / e	i = c x g / e	k
Uncertainty Component	Sec.	Tol. (± %)	Prob. Dist.	Div.	c _i (1-g)	c _i (10-g)	1-g u _i (±%)	10-g u _i (±%)	v _i
Measurement System									
Probe Calibration (k=1)	E.2.1	4.7	R	1.73	0.707	0.707	1.9	1.9	∞
Axial Isotropy	E.2.2	9.6	R	1.73	0.707	0.707	3.9	3.9	∞
Hemispherical Isotropy	E.2.2	1.0	R	1.73	1	1	0.6	0.6	∞
Boundary Effect	E.2.3	4.7	R	1.73	1	1	2.7	2.7	∞
Linearity	E.2.4	1.0	R	1.73	1	1	0.6	0.6	∞
System Detection Limits	E.2.5	1.0	N	1	1	1	1.0	1.0	∞
Readout Electronics	E.2.6	0.8	R	1.73	1	1	0.5	0.5	∞
Response Time	E.2.7	2.6	R	1.73	1	1	1.5	1.5	∞
Integration Time	E.2.8	4.7	R	1.73	0.707	0.707	1.9	1.9	∞
RF Ambient Conditions	E.6.1	3.0	R	1.73	1	1	1.7	1.7	∞
Probe Positioner Mechanical Tolerance (corresponds to the mechanical constrains of the robot)	E.6.2	0.4	R	1.73	1	1	0.2	0.2	∞
Probe Positioning with respect to Phantom Shell	E.6.3	2.9	R	1.73	1	1	1.7	1.7	∞
Extrapolation, interpolation and Integration Algorithms for Max. SAR Evaluation	E.5	1.0	R	1.73	1	1	0.6	0.6	∞
Dipole									
Dipole Axis to Liquid Distance	8, E.4.2	1.0	R	1.73	1	1	0.6	0.6	∞
Input Power and SAR Drift Measurement	8, 6.6.2	5.0	R	1.73	1	1	2.9	2.9	∞
Phantom and Tissue Parameters									
Phantom Uncertainty - shell thickness tolerance	E.3.1	4.0	R	1.73	1	1	2.3	2.3	∞
Liquid Conductivity - deviation	E.3.2	4.3	R	1.73	0.64	0.43	1.59	1.07	∞



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from target values (5)									
Liquid Conductivity - measurement uncertainty (6)	E.3.3	6.20	R	1.73	0.64	0.43	2.29	1.54	∞
Liquid Permittivity - deviation from target values (5)	E.3.2	3.7	R	1.73	0.6	0.49	1.28	1.05	∞
Liquid Permittivity - measurement uncertainty (6)	E.3.3	6.08	R	1.73	0.6	0.49	2.11	1.72	∞
Combined Standard Uncertainty			RSS				9.37	9.03	
Expanded Uncertainty (95% C.L.)							18.74	18.05	



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Table 2a: Uncertainty Budget for the Device Under Test with DASY3 System

<i>a</i>	<i>b</i>	<i>c</i>	<i>d</i>	$e = f(d,k)$	<i>f</i>	<i>g</i>	$h = c \times f / e$	$i = c \times g / e$	<i>k</i>
Uncertainty Component	Sec.	Tol. (± %)	Prob. Dist.	Div.	$c_i (1-g)$	$c_i (10-g)$	1-g $u_i (\pm\%)$	10-g $u_i (\pm\%)$	v_i
Measurement System									
Probe Calibration ($k=1$)	E.2.1	4.8	N	1	1	1	4.8	4.8	∞
Axial Isotropy	E.2.2	4.7	R	1.73	0.707	0.707	1.9	1.9	∞
Hemispherical Isotropy	E.2.2	9.6	R	1.73	0.707	0.707	3.9	3.9	∞
Boundary Effect	E.2.3	8.3	R	1.73	1	1	4.8	4.8	∞
Linearity	E.2.4	4.7	R	1.73	1	1	2.7	2.7	∞
System Detection Limits	E.2.5	1.0	R	1.73	1	1	0.6	0.6	∞
Readout Electronics	E.2.6	1.0	N	1	1	1	1.0	1.0	∞
Response Time	E.2.7	0.8	R	1.73	1	1	0.5	0.5	∞
Integration Time	E.2.8	1.4	R	1.73	1	1	0.8	0.8	∞
RF Ambient Conditions	E.6.1	3.0	R	1.73	1	1	1.7	1.7	∞
Probe Positioner Mechanical Tolerance (corresponds to the mechanical constrains of the robot)	E.6.2	0.4	R	1.73	1	1	0.2	0.2	∞
Probe Positioning with respect to Phantom Shell	E.6.3	2.9	R	1.73	1	1	1.7	1.7	∞
Extrapolation, interpolation and Integration Algorithms for Max. SAR Evaluation	E.5	3.9	R	1.73	1	1	2.3	2.3	∞
Test sample Related									
Test Sample Positioning	E.4.2	1.0	N	1	1	1	1.2	1.2	4
Device Holder Uncertainty	E.4.1	2.0	R	1.73	1	1	0.7	0.7	4
Output Power Variation - SAR drift measurement (4)	6.6.2	5.0	R	1.73	1	1	2.9	2.9	∞
Phantom and Tissue Parameters									



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Phantom Uncertainty (shape and thickness tolerances)	E.3.1	4.0	R	1.73	1	1	2.3	2.3	∞
Liquid Conductivity - deviation from target values (5)	E.3.2	4.3	R	1.73	0.64	0.43	1.6	1.1	∞
Liquid Conductivity - measurement uncertainty (6)	E.3.3	6.20	R	1.73	0.64	0.43	2.3	1.5	∞
Liquid Permittivity - deviation from target values (5)	E.3.2	3.7	R	1.73	0.6	0.49	1.3	1.0	∞
Liquid Permittivity - measurement uncertainty (6)	E.3.3	6.08	R	1.73	0.6	0.49	2.1	1.7	∞
Combined Standard Uncertainty			RSS				10.73	10.42	
Expanded Uncertainty (95% CONFIDENCE LEVEL)			K=2				21.45	20.84	



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Table 2b: Uncertainty Budget for the Device Under Test with DASY4 System

<i>a</i>	<i>b</i>	<i>c</i>	<i>d</i>	$e = f(d,k)$	<i>f</i>	<i>g</i>	$h = c \times f / e$	$i = c \times g / e$	<i>k</i>
Uncertainty Component	Sec.	Tol. (± %)	Prob. Dist.	Div.	c_i (1-g)	c_i (10-g)	1-g u_i (±%)	10-g u_i (±%)	v_i
Measurement System									
Probe Calibration ($k=1$)	E.2.1	4.8	N	1	1	1	4.8	4.8	∞
Axial Isotropy	E.2.2	4.7	R	1.73	0.707	0.707	1.9	1.9	∞
Hemispherical Isotropy	E.2.2	9.6	R	1.73	0.707	0.707	3.9	3.9	∞
Boundary Effect	E.2.3	1.0	R	1.73	1	1	0.6	0.6	∞
Linearity	E.2.4	4.7	R	1.73	1	1	2.7	2.7	∞
System Detection Limits	E.2.5	1.0	R	1.73	1	1	0.6	0.6	∞
Readout Electronics	E.2.6	1.0	N	1	1	1	1.0	1.0	∞
Response Time	E.2.7	0.8	R	1.73	1	1	0.5	0.5	∞
Integration Time	E.2.8	2.6	R	1.73	1	1	1.5	1.5	∞
RF Ambient Conditions	E.6.1	3.0	R	1.73	1	1	1.7	1.7	∞
Probe Positioner Mechanical Tolerance (corresponds to the mechanical constrains of the robot)	E.6.2	0.4	R	1.73	1	1	0.2	0.2	∞
Probe Positioning with respect to Phantom Shell	E.6.3	2.9	R	1.73	1	1	1.7	1.7	∞
Extrapolation, interpolation and Integration Algorithms for Max. SAR Evaluation	E.5	1.0	R	1.73	1	1	0.6	0.6	∞
Test sample Related									
Test Sample Positioning	E.4.2	1.0	N	1	1	1	1.2	1.2	4
Device Holder Uncertainty	E.4.1	2.0	R	1.73	1	1	0.7	0.7	4
Output Power Variation - SAR drift measurement (4)	6.6.2	5.0	R	1.73	1	1	2.9	2.9	∞
Phantom and Tissue Parameters									



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Phantom Uncertainty (shape and thickness tolerances)	E.3.1	4.0	R	1.73	1	1	2.3	2.3	∞
Liquid Conductivity - deviation from target values (5)	E.3.2	4.3	R	1.73	0.64	0.43	1.6	1.1	∞
Liquid Conductivity - measurement uncertainty (6)	E.3.3	6.20	R	1.73	0.64	0.43	2.3	1.5	∞
Liquid Permittivity - deviation from target values (5)	E.3.2	3.7	R	1.73	0.6	0.49	1.3	1.0	∞
Liquid Permittivity - measurement uncertainty (6)	E.3.3	6.08	R	1.73	0.6	0.49	2.1	1.7	∞
Combined Standard Uncertainty			RSS				9.46	9.12	
Expanded Uncertainty (95% CONFIDENCE LEVEL)			K=2				18.91	18.23	



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Table 3a. Values for ϵ'

Uncertainty Component	Tolerance ($\pm\%$)	Probability Distribution	Divisor	c_i	Standard Uncertainty ($\pm\%$)	v_i or v_{eff}
Repeatability (n repeats)	0.97	N	1	1	0.97	4
Network analyzer uncertainty sources	8.38	R	1.73	1	4.83	∞
Dielectric Error Sources	5.93	R	1.73	1	3.42	∞
Combined standard uncertainty					6.08	

Table 3b. Values for σ

Uncertainty Component	Tolerance ($\pm\%$)	Probability Distribution	Divisor	c_i	Standard Uncertainty ($\pm\%$)	v_i or v_{eff}
Repeatability (n repeats)	1.85	N	1	1	1.85	4
Network analyzer uncertainty sources	8.38	R	1.73	1	4.83	∞
Dielectric Error Sources	5.93	R	1.73	1	3.42	∞
Combined standard uncertainty					6.20	

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Appendix 6

Photographs of the Device Under Test



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a. Front



b. Back



c. Side

Views of Device



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Front View



Back View

Front and Back views of carry accessory model ICE-25.



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Front View



Back View

Front and Back views of carry accessory model ICT-14.

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View of Hands-free Accessory HPB-20



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Position of device against head phantom

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Position of device against head phantom in the tilted position



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Position of device against flat phantom using a 15mm spacer with hands free accessory (HPB-20).



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Position of device against flat phantom using a 15mm spacer with hands free accessory (HPB-20).



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Position of device against flat phantom using carry accessory ICE25 with hands free accessory (HPB-20).



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Position of device against flat phantom using carry accessory ICT14 with hands free accessory (HPB-20).