Prepared (also subject responsible if other)		No.	
SEM/CV/PF/P Gerard Hayes and Rodney Dixon		REP 2005 008 W600i 02	
Approved	Checked		
SEM/CV/PF/P Gerard Hayes		A	X:\SAR Chamber\FCC reports\W600I\Final Reports\FCCW600I.doc

Appendix 4

Probe Calibration Certificates

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%	$\mu V/(V/m)^2$	DCP X	**94** mV
NormY	**1.84** ± 10.1%	$\mu V/(V/m)^2$	DCP Y	**94** mV
NormZ	**1.89** ± 10.1%	$\mu V/(V/m)^2$	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_{be} [%]	Without Correction Algorithm	8.4	4.3
SAR_{be} [%]	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_{be} [%]	Without Correction Algorithm	12.2	8.2
SAR_{be} [%]	With Correction Algorithm	0.8	0.1

Sensor Offset

Probe Tip to Sensor Center **2.7** mm

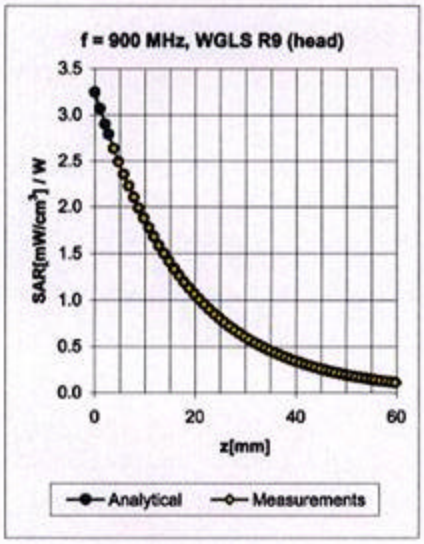
The reported uncertainty of measurement is stated as the standard uncertainty of measurement multiplied by the coverage factor k=2, which for a normal distribution corresponds to a coverage probability of approximately 95%.

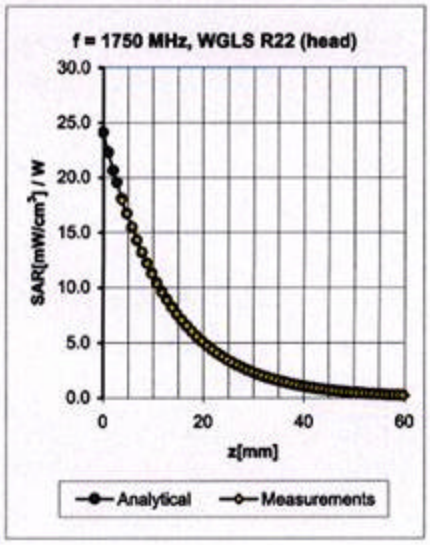
[A] The uncertainties of NormX,Y,Z do not affect the E^2-field uncertainty inside TSL (see Page 8).

[B] Numerical linearization parameter: uncertainty not required.

ET3DV6 SN:1586 **May 26, 2005**

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.

ET3DV6 SN:1587 **May 26, 2005**

DASY - Parameters of Probe: ET3DV6 SN:1587

Sensitivity in Free Space[A]

NormX	**2.05** ± 10.1%	$\mu V/(V/m)^2$	DCP X	**95** mV
NormY	**1.92** ± 10.1%	$\mu V/(V/m)^2$	DCP Y	**95** mV
NormZ	**1.79** ± 10.1%	$\mu V/(V/m)^2$	DCP Z	**95** mV

Diode Compression[B]

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_{be} [%]	Without Correction Algorithm	8.1	4.4
SAR_{be} [%]	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_{be} [%]	Without Correction Algorithm	12.4	8.5
SAR_{be} [%]	With Correction Algorithm	0.5	0.1

Sensor Offset

Probe Tip to Sensor Center **2.7** mm

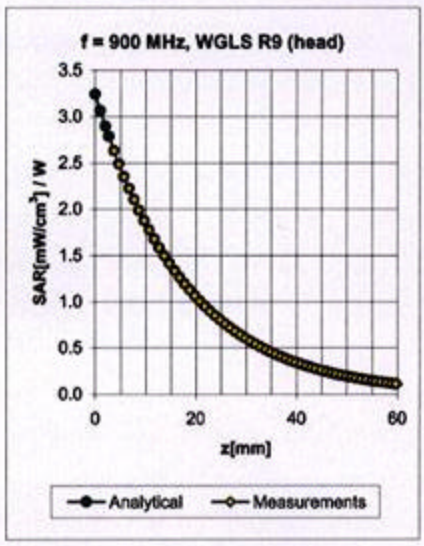
The reported uncertainty of measurement is stated as the standard uncertainty of measurement multiplied by the coverage factor k=2, which for a normal distribution corresponds to a coverage probability of approximately 95%.

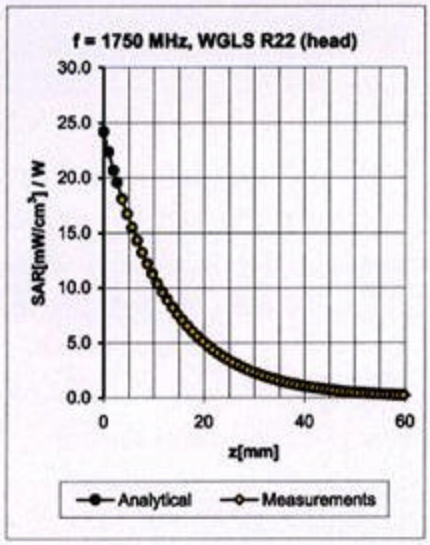
[A] The uncertainties of NormX,Y,Z do not affect the E^2-field uncertainty inside TSL (see Page 8).

[B] Numerical linearization parameter: uncertainty not required.

ET3DV6 SN:1587 **May 26, 2005**

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%	0.60	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.

Appendix 5

Measurement Uncertainty Budget

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)	E2.1	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 from target values (5)	E.3.2	4.3	R	1.73	0.64	0.43	1.59	1.07	∞

Prepared (also subject responsible if other)		No.	
SEM/CV/PF/P Gerard Hayes and Rodney Dixon		REP 2005 008 W600i 02	
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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	

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)	E2.1	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 from target values (5)	E.3.2	4.3	R	1.73	0.64	0.43	1.59	1.07	∞

Prepared (also subject responsible if other)		No.	
SEM/CV/PF/P Gerard Hayes and Rodney Dixon		REP 2005 008 W600i 02	
Approved	Checked		
SEM/CV/PF/P Gerard Hayes		A	X:\SAR Chamber\FCC reports\W600I\Final Reports\FCCW600I.doc

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	

Table 2a: Uncertainty Budget for the Device Under Test with 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)	E2.1	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	1.2	N	1	1	1	1.2	1.2	4
Device Holder Uncertainty	E.4.1	1.0	R	1.73	1	1	0.6	0.6	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									

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				**10.72**	**10.41**	
Expanded Uncertainty (95% CONFIDENCE LEVEL)			K=2				**21.45**	**20.82**	

Table 2b: Uncertainty Budget for the Device Under Test with 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)	E2.1	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	1.2	N	1	1	1	1.2	1.2	4
Device Holder Uncertainty	E.4.1	1.0	R	1.73	1	1	0.6	0.6	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									

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				**9.43**	**9.08**	
Expanded Uncertainty (95% CONFIDENCE LEVEL)			K=2				**18.87**	**18.15**	

Table 3a. Values for e'

Uncertainty Component	Tolerance (±%)	Probability Distribution	Divisor	c_i	Standard Uncertainty (±%)	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 s

Uncertainty Component	Tolerance (±%)	Probability Distribution	Divisor	c_i	Standard Uncertainty (±%)	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**	

Appendix 6

Photographs of the Device Under Test

a. Front

b. Back

View of Device (Open)

a. Front

b. Back

View of Device (Closed)

a. Side

View of Device (side)

View of Hands-free Accessory

a. Side

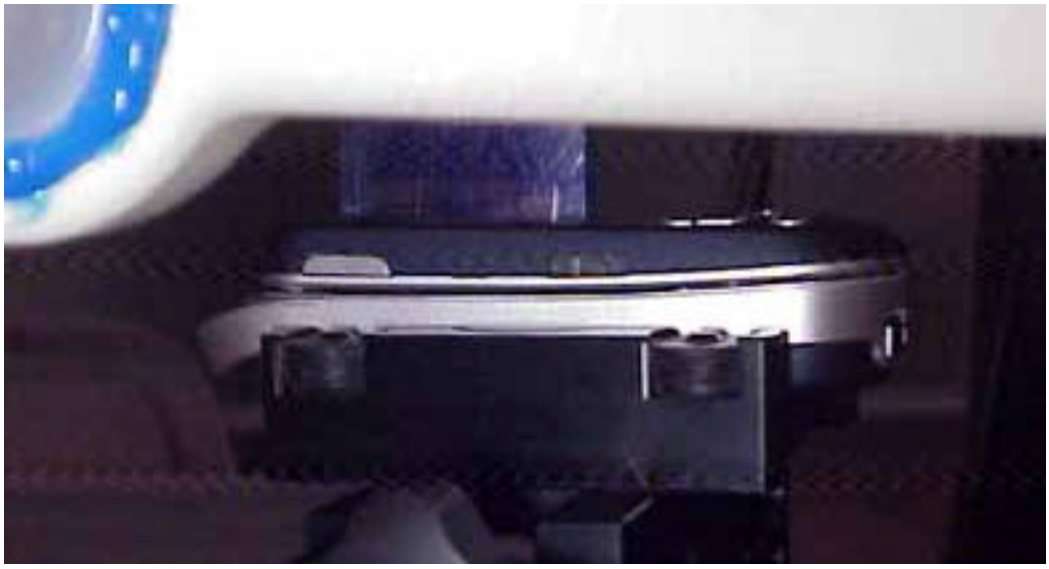
View of Carry Case ICE30 (side)

Position of device against head phantom using the “cheek” closed position

Position of device against head phantom using the “tilt” closed position

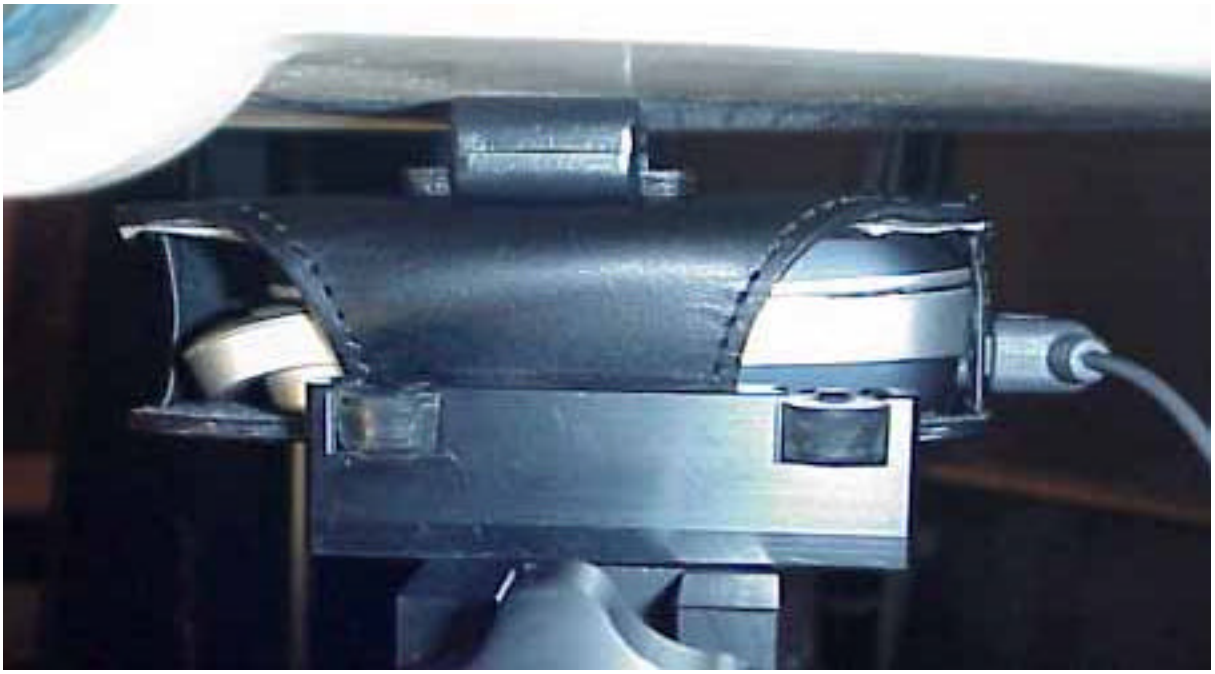
Position of device against head phantom using the “cheek” open position

Position of device against head phantom using the “tilt” open position

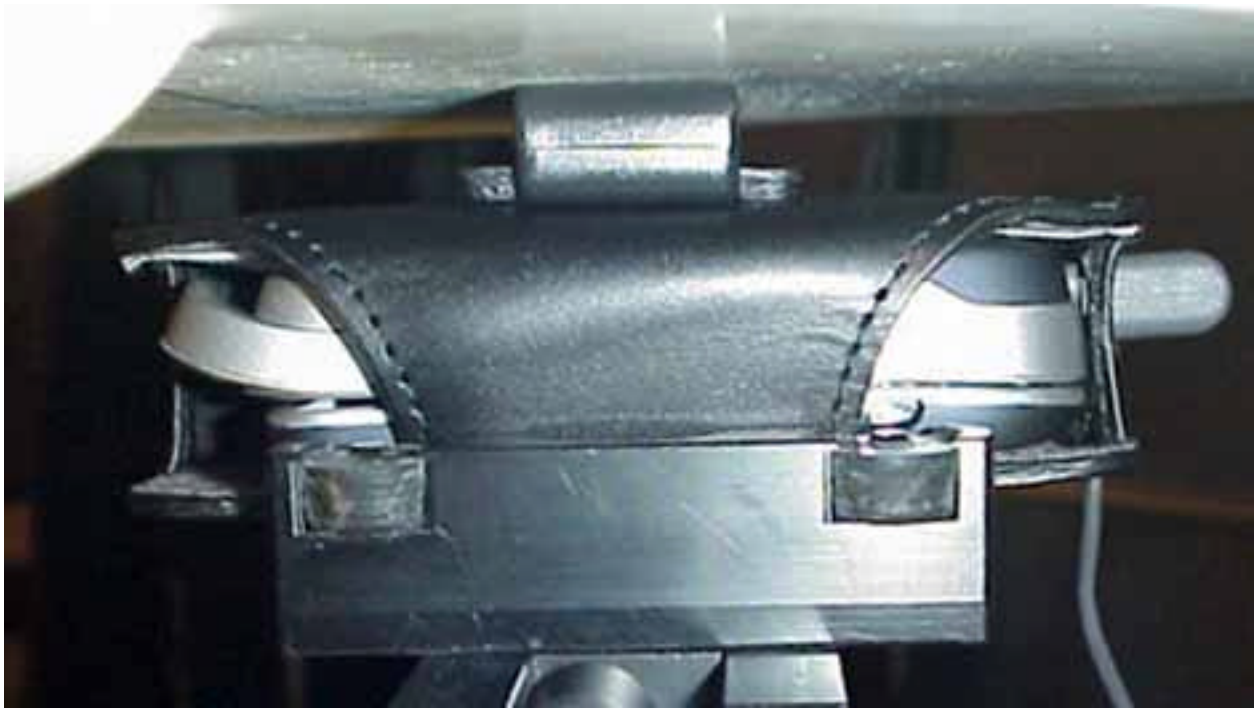


Position with front of device against flat phantom using a 15MM SPACER.

Position with back of device against flat phantom using a 15MM spacer.



Position with front of device against flat phantom using a ICE30 carry case.



Position with back of device against flat phantom using a ICE30 carry case.