



US 20170119466A1

(19) **United States**(12) **Patent Application Publication**
HIRVONEN et al.(10) **Pub. No.: US 2017/0119466 A1**(43) **Pub. Date: May 4, 2017**(54) **AUTOMATED SYSTEM FOR
LASER-ASSISTED DERMATOLOGICAL
TREATMENT AND CONTROL METHOD***A61B 34/00* (2006.01)*A61B 34/30* (2006.01)*A61B 34/10* (2006.01)(71) Applicant: **CRYOTECH NORDIC OU**, Tallinn
(EE)(52) **U.S. Cl.**CPC *A61B 18/203* (2013.01); *A61B 34/30*
(2016.02); *A61B 34/10* (2016.02); *A61B 34/25*
(2016.02); *A61B 90/361* (2016.02); *A61B*
2018/00452 (2013.01)(72) Inventors: **Vesa HIRVONEN**, Espoo (FI); **Jan**
EKLUND, Vantaa (FI); **Juha Tapani**
YLIOLLITERVO, Jarvenpaa (FI)

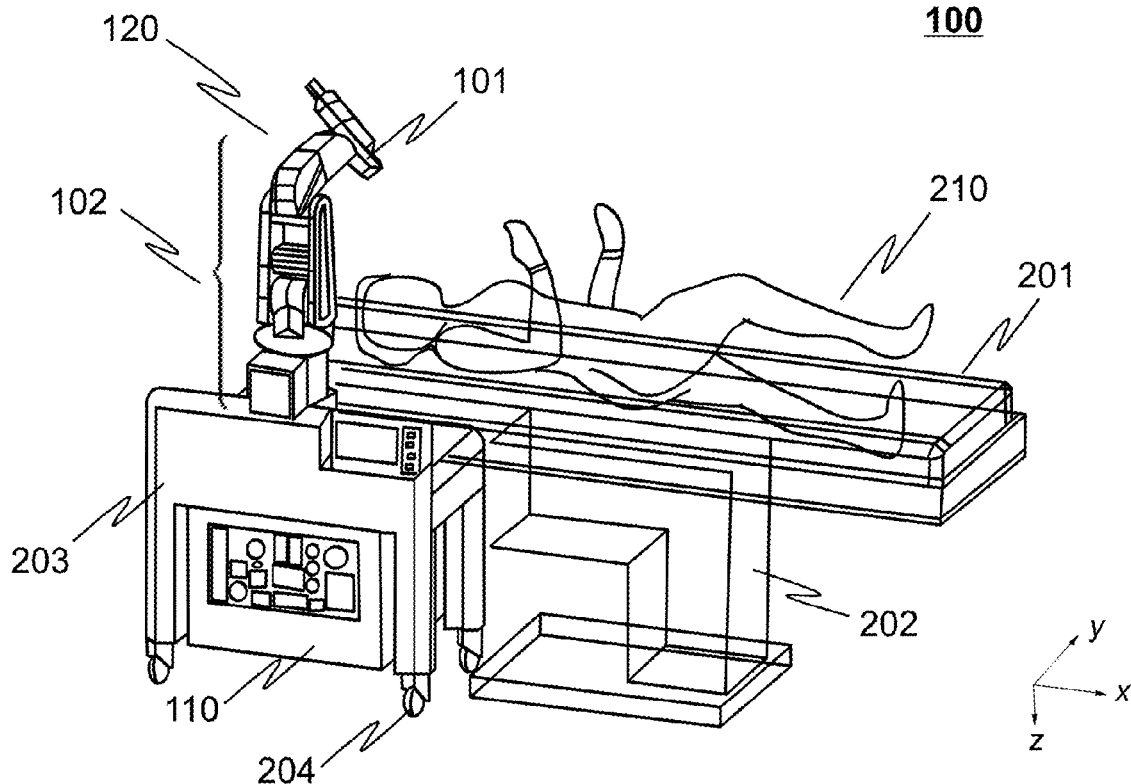
(57)

ABSTRACT(21) Appl. No.: **15/337,112**(22) Filed: **Oct. 28, 2016**(30) **Foreign Application Priority Data**

Nov. 2, 2015 (FI) 20155784

Publication Classification(51) **Int. Cl.***A61B 18/20* (2006.01)*A61B 90/00* (2006.01)

A system **100** for automated laser-assisted dermatological treatment is provided; the system includes a robot arm assembly **120**, including a laser head **101** coupled to the robot arm **102** and a controlling unit **110**. The system is configured to remove an undesirable dermatological condition from skin by directing laser energy to a pre-defined skin surface area intended for treatment essentially in an absence of human attendance. A method for real-time controlling an automated laser-assisted removal of undesirable dermatological condition from skin implemented by a system **100** and a computer program product for causing the computer to execute the method are further provided.



100

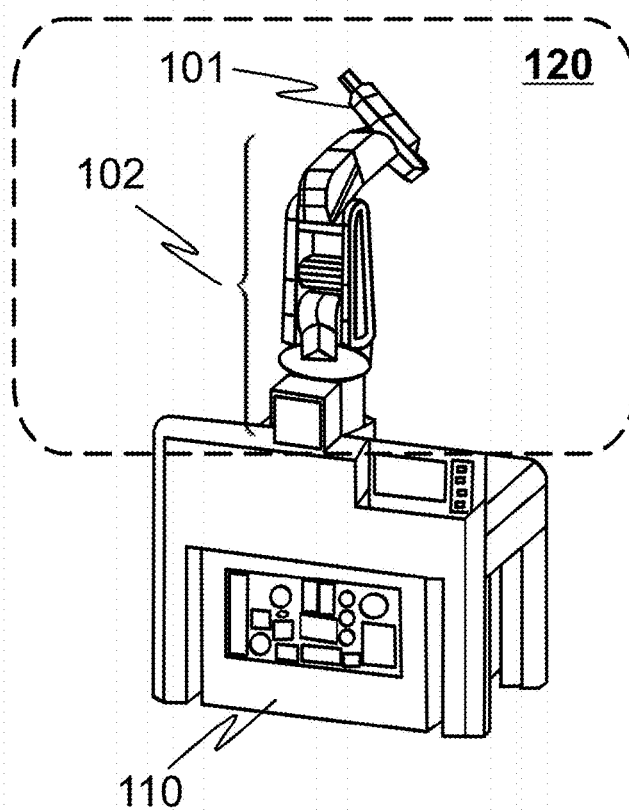


Figure 1

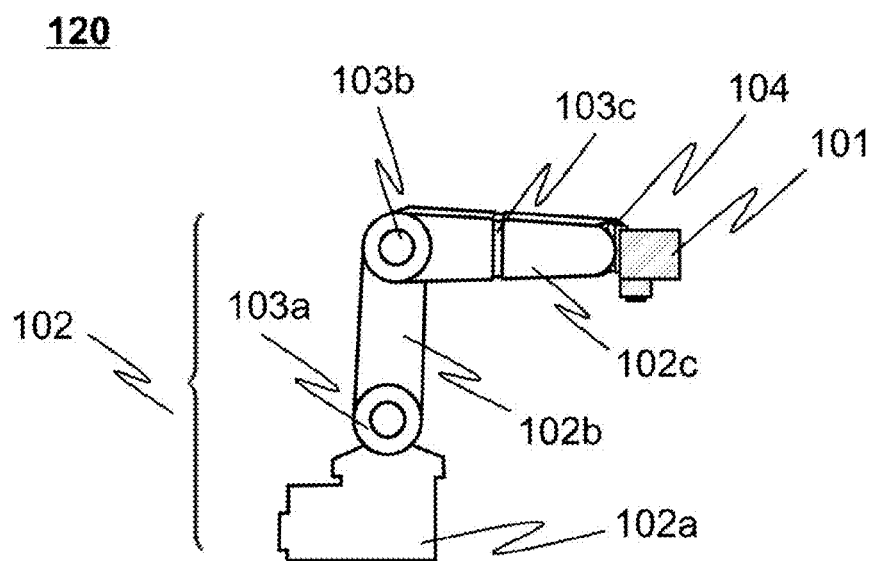


Figure 2A

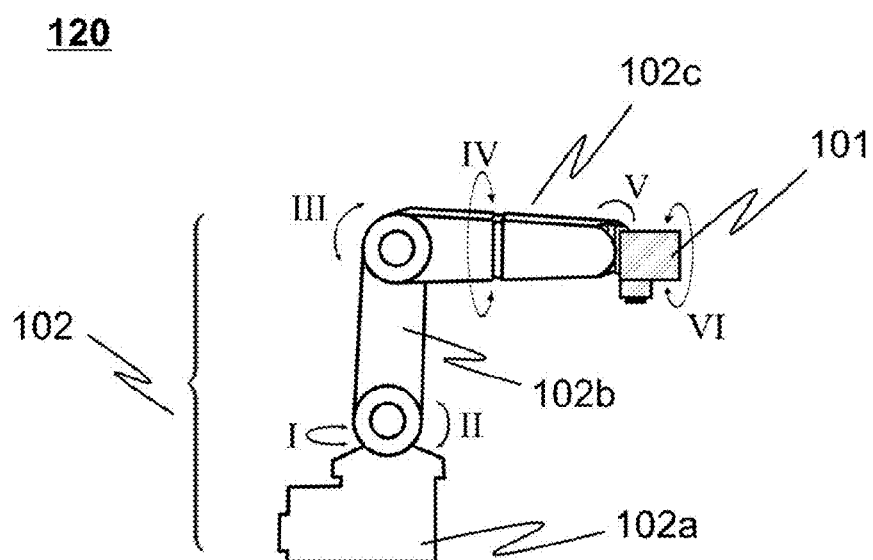


Figure 2B

100

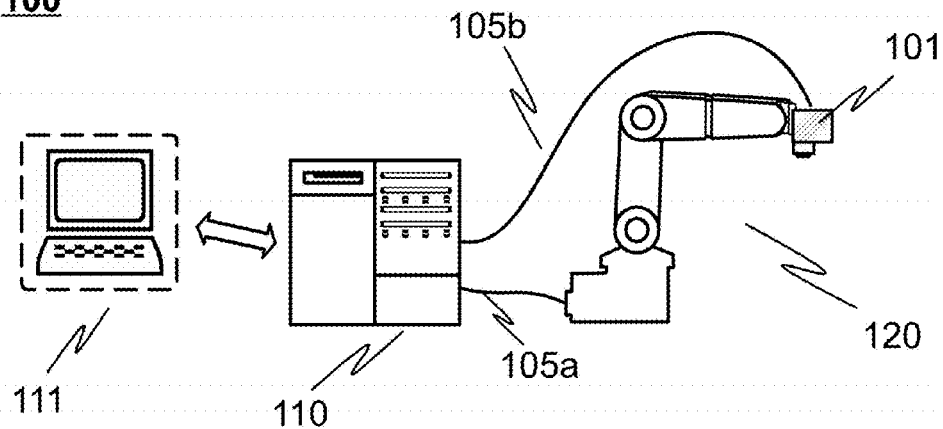


Figure 3

101

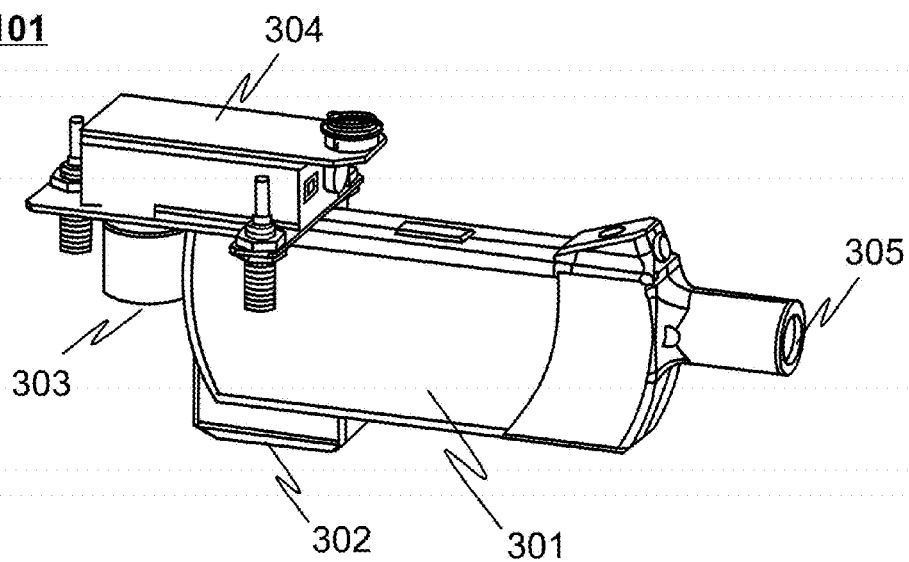


Figure 4

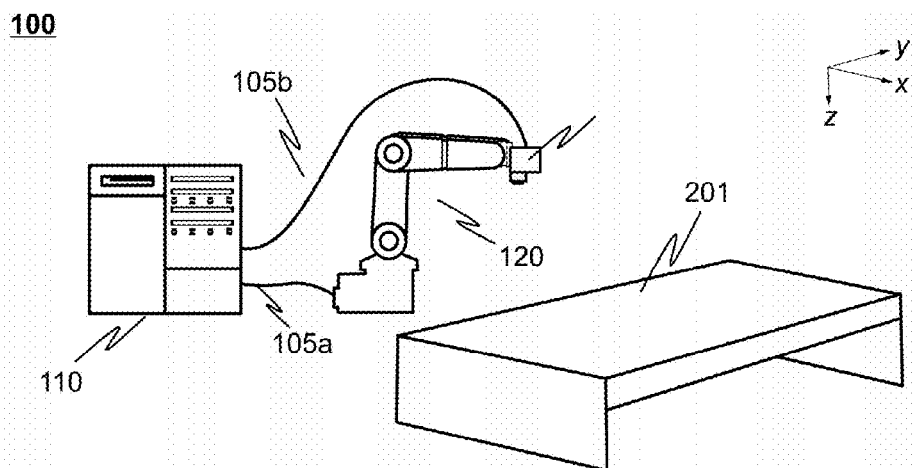


Figure 5A

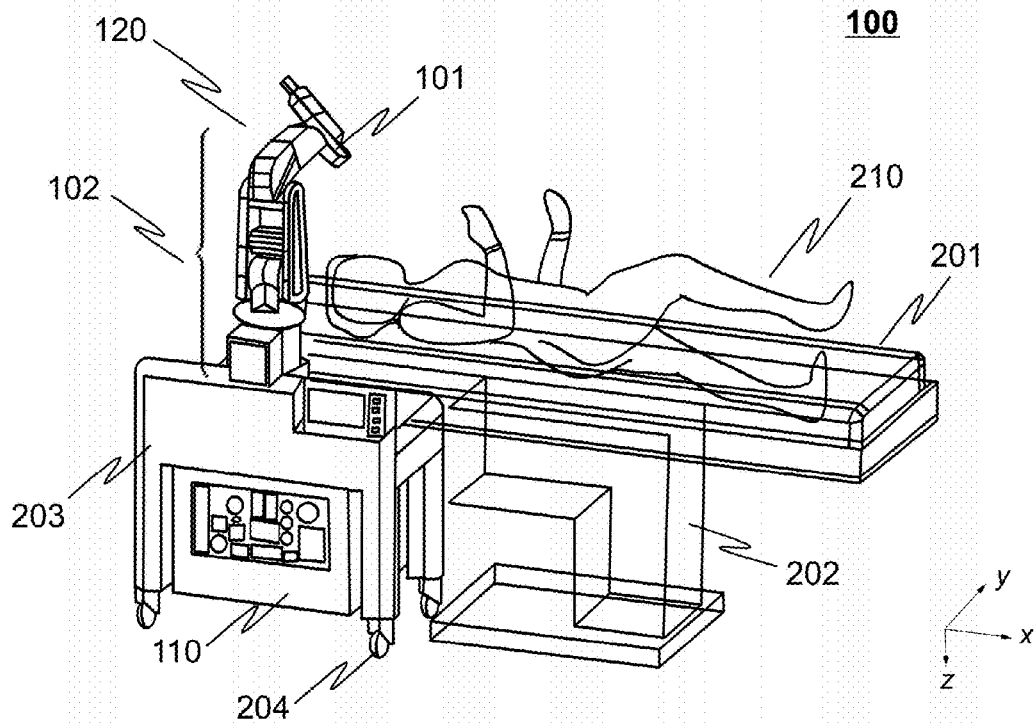


Figure 5B

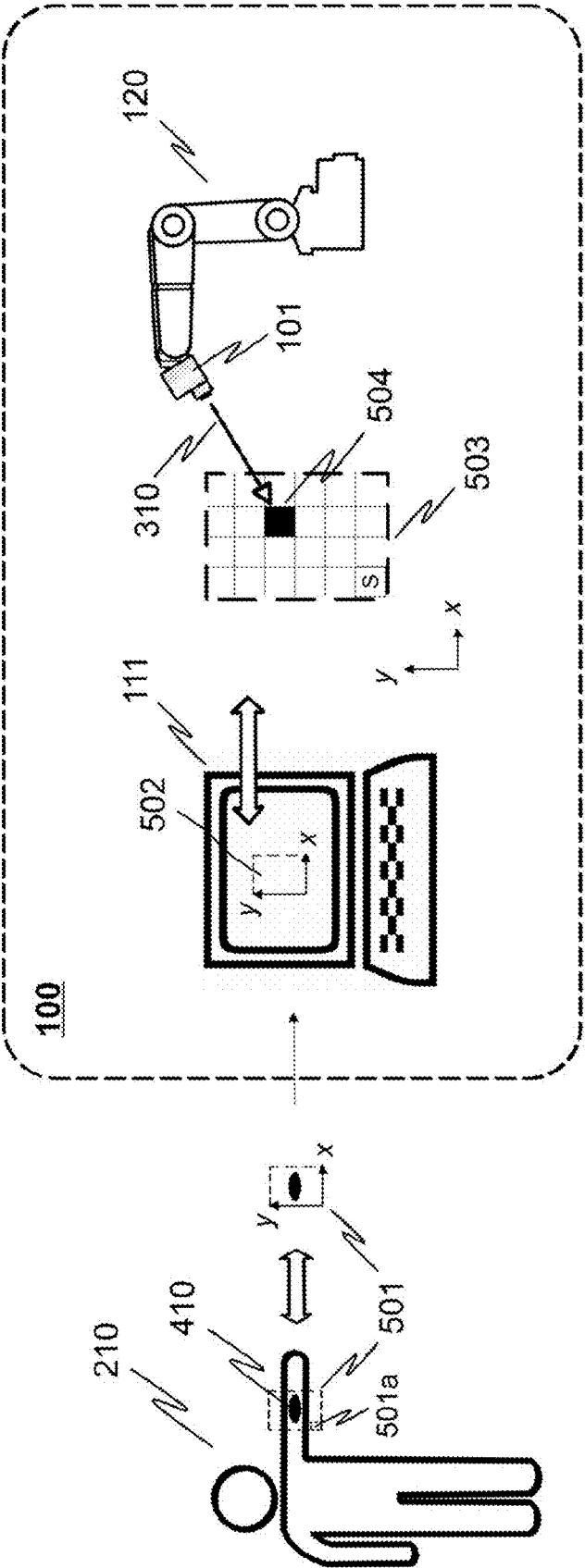


Figure 6

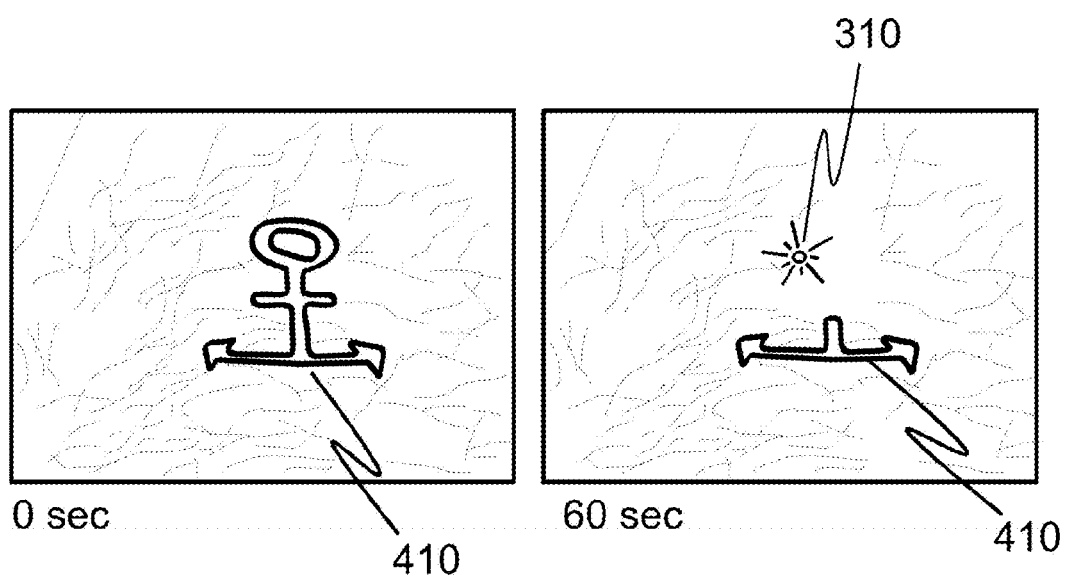


Figure 7

AUTOMATED SYSTEM FOR LASER-ASSISTED DERMATOLOGICAL TREATMENT AND CONTROL METHOD

FIELD OF THE INVENTION

[0001] The present invention generally relates to laser-assisted dermatological treatment systems and methods; more particularly the invention concerns an automated, robot arm assembly based system for laser-assisted removal of tattoos, scars and/or pigmented dermatological conditions from skin and an associated method for controlling thereof.

BACKGROUND

[0002] The attempts to remove tattoos date back to the origins of tattooing—creating permanent marks or designs on the body—an ancient practice for identification and/or decoration of an individual, which has been in existence since the early beginnings of modern civilization. Since in recent decades a trend for tattooing became a matter of individual choice to serve the purpose of self-expression, the patients seek tattoo removal on a more frequent and routine basis, accordingly.

[0003] Since the present-day tattooing technology involves injection of ink particles into a skin dermis (a layer of skin beneath epidermis) at a depth about 1.1-2.9 mm below the skin surface, removal of a tattoo requires elimination of said pigment from the skin, accordingly. Sophisticated modern laser-assisted methods target the tattoo ink and break it up into smaller particles, which are naturally absorbed by the body's immune system.

[0004] Laser-assisted tattoo removal by argon and carbon dioxide lasers has been piloted at 1970s; however, these lasers have caused non-specific ablation of tissue at a tattoo site when targeting water molecules as chromophores and in majority of cases have failed to remove the tattoo completely while leaving scars. Recent techniques utilize quality-switched (QS) lasers, such as an alexandrite, ruby and neodymium:yttrium-aluminum-garnet (Nd:YAG) lasers, for example, capable of producing nanosecond range pulses at very high peak power. Moreover, an apparatus for tattoo removal utilizing lasers with pulse duration in a picosecond range is disclosed in the U.S. Pat. Nos. 7,586,957 and 7,929,579 and in the U.S. patent application publication No. 2015/180193. A device for tattoo removal utilizing a titanium doped sapphire (Ti:Sapphire) solid state laser with pulse duration in a femtosecond range is further disclosed in the U.S. Pat. No. 8,187,256.

[0005] The abovementioned laser-assisted devices and systems are still constrained with limitations caused by an ultimate dependence thereof on human factor. In other words, modern technology involves devices and systems for tattoo removal that are all human (manual) operated. In this regard, localization of pigment on a patient's skin and provision of pulses of electromagnetic radiation to remove said pigment are performed by an operator. As a consequence, accuracy, precision, speed and overall efficiency of the treatment are to a certain extent biased by an operator performance error. Since standardization of manually performed tattoo and/or scar removal procedures in terms of precision vs speed parameters is hampered, the treatment duration is often overextended and the patient is caused to experience unnecessary pain or at least discomfort. The

aforesaid applies equally well to other undesirable pigmented dermatological condition (lesions) of varying nature.

[0006] If tattooing becomes even more widespread than it is today, the request for tattoo removal will increase exponentially. In this regard, a demand for more effective permanent tattoo removal solutions still exists.

SUMMARY OF THE INVENTION

[0007] An objective of the present invention is to at least alleviate one or more problems arising from the limitations and disadvantages of the related art. The objective is achieved by various embodiments of an automated system for laser-assisted dermatological treatment and a method for controlling thereof.

[0008] Thereby, in one aspect of the invention an automated system for laser-assisted removal of an undesirable dermatological condition from skin is provided, according to what is defined in the independent claim 1. The system thus comprises a robot arm assembly, comprising an end effector in the form of a laser head coupled to an articulated robot arm and a controlling unit. The system is configured to sequentially direct, via the laser head, laser energy to a number of pre-determined, individual portions of skin identified within the boundaries of a pre-defined skin surface area intended for treatment and at least partly comprising said undesirable dermatological condition, wherein the controlling unit is configured to adjust positioning of the robot arm assembly with respect to each individual skin portion and directing laser energy thereto in real time, said controlling unit is further configured to receive a series of parameter data obtainable from an at least one proximity sensor and an image acquisition device provided within the laser head and, based on said parameter data, to issue a series of updated commands to each of the robot arm and the laser head continuously throughout the treatment.

[0009] In one preferred embodiment the system further comprises a processing unit configured to generate and store a virtual model of the pre-defined skin surface area intended for treatment, to identify a number of sub-areas within said model, wherein each sub-area corresponds to the individual skin portion within the boundaries of the pre-defined skin surface area intended for treatment, and to communicate the data on thus identified sub-areas to the controlling unit and/or the robot arm assembly.

[0010] The processing unit of the system is preferably configured to update and adjust the stored virtual model based on the series of parameter data received from the controlling unit and/or the robot arm assembly and to communicate thus updated and adjusted model data to the controlling unit and/or the robot arm assembly, wherein updating, adjusting and communicating the model data is executed in real time and continuously throughout the treatment.

[0011] In some alternative embodiment the controlling unit is combined with the processing unit.

[0012] In some further embodiment the system further comprises a treatment platform for accommodating a patient.

[0013] In some embodiment the undesirable dermatological condition to be treated is tattoo. In some other embodiments the undesirable dermatological condition to be treated is selected from the group consisting of: scars, birthmarks, moles, freckles, lentigines, solar lentigo and hyperpigmentation.

[0014] In another aspect of the invention a method for real-time controlling an automated laser-assisted removal of undesirable dermatological condition from skin implemented by a system according to the previous aspect is further provided, according to what is defined in the independent claim 12.

[0015] In still another aspect a computer program product embodied in a non-transitory computer readable medium and comprising computer code for causing the computer to execute the method according to one of the previous aspects is provided, according to what is defined in the independent claim 14.

[0016] The utility of the present invention arises from a variety of reasons depending on each particular embodiment thereof. At first, the system provides for fast and precise removal of the undesirable dermatological condition from skin in an essentially operator-independent manner, thus being free of errors caused by human factor. Any laser-assisted removal of undesirable dermatological conditions from skin inevitably results in ablating also the unaffected skin regions, when performed manually by the operator. For example, upon laser-assisted tattoo removal by hand the operator manually targets laser pulses onto the patient's skin; however, manually directed lasing beam hits, along with the pigmented skin regions, also the ones free of pigment. Even the treatment performed by the experienced personnel is not error-free. By utilization of the system provided hereby this operator performance error related drawback can be completely eliminated.

[0017] The system further allows for speeding up the treatment and/or for accomplishing the treatment during a reduced number of sessions as compared to the manual same, thus reducing costs and avoiding unnecessary discomfort.

[0018] The term "dermatological condition" is utilized within the present disclosure as a synonym of the term "skin condition".

[0019] The expression "a number of" refers herein to any positive integer starting from one (1), e.g. to one, two, or three.

[0020] Different embodiments of the present invention will become apparent by consideration of the detailed description and accompanying drawings.

BRIEF DESCRIPTION OF THE DRAWINGS

[0021] FIG. 1 is a perspective view of an automated system 100 for automated laser-assisted dermatological treatment in accordance to some aspect of the invention.

[0022] FIG. 2A is a schematic view of a robot arm assembly 120 provided within the system 100;

[0023] FIG. 2B illustrates rotational axes of the assembly of Fig. 2A.

[0024] FIG. 3 is a schematic view of the system 100.

[0025] FIG. 4 shows is a perspective view of a laser head provided within the assembly 120 and the system 100, accordingly.

[0026] FIGS. 5A and 5B show a schematic view and a perspective view, accordingly, of the system 100 implemented according to some embodiment.

[0027] FIG. 6 schematically illustrates a process for the automated laser-assisted dermatological treatment mediated by the system 100.

[0028] FIG. 7 shows a comparative example for tattoo removal from patient's skin executed by the system 100; the

photograph on the left shows a tattoo at the beginning of the treatment (0 sec) and the photograph on the right—the same tattoo 60 sec later.

DETAILED DESCRIPTION OF THE EMBODIMENTS

[0029] Detailed embodiments of the present invention are disclosed herein with the reference to accompanying drawings. The same reference characters are used throughout the drawings to refer to same members. Following citations are used for the members:

[0030] 100—an automated system for laser-assisted dermatological treatment;

[0031] 101—a laser head;

[0032] 102—a robot arm, wherein: 102a is a base; 102b is an upper arm and 102c is a forearm;

[0033] 103a-c—joint connectors, wherein: 103a is a shoulder hinge; 103b is an elbow hinge; and

[0034] 103c is a rotary joint at the forearm;

[0035] 104—a rotatable joint adapter/mounting means for the laser head;

[0036] 105a, 105b—communication lines between the control unit and the robot arm and between the control unit and the laser head, respectively;

[0037] 110—a controlling unit;

[0038] 111—a processing unit (a computer);

[0039] 120—a robot arm assembly

[0040] 201—a treatment platform;

[0041] 202—stairs (auxiliary appliance);

[0042] 203—a supporting rack (auxiliary appliance);

[0043] 204—wheels for the supporting rack (auxiliary appliance);

[0044] 210—a patient;

[0045] 301—a casing (laser head);

[0046] 302—a lasing beam aperture;

[0047] 303—an image acquisition device and proximity sensor(s);

[0048] 304—a fastening element;

[0049] 305—a cable port;

[0050] 310—a lasing beam;

[0051] 410—an undesirable dermatological condition to be treated;

[0052] 501—a skin surface area intended for treatment;

[0053] 501a—an individual skin portion within the area 501;

[0054] 502—a virtual field model of the area 501;

[0055] 503—a grid;

[0056] 504—a sub-area within the model 502 corresponding the skin portion 501a.

[0057] FIG. 1 illustrates at 100 the concept underlying various embodiments of an automated system for laser-assisted dermatological treatment in accordance with some aspect of the present invention. In preferred embodiment the laser-assisted dermatological treatment comprises removal of an undesirable dermatological condition from skin. In the most preferred embodiment the undesirable dermatological condition is tattoo.

[0058] In some other embodiment the undesirable dermatological condition is a scar. The scar to be treated may be caused by any of an accident, infection, inflammation or surgery. In further embodiments, the undesirable dermatological condition is a pigmented dermatological condition

(lesion), selected from the group consisting of birthmarks, moles, freckles, lentigines, solar lentigo and various types of hyperpigmentation.

[0059] By the term “automated” we refer in the present disclosure to the system, configured to perform the laser-assisted dermatological treatment comprising removal of an undesirable dermatological condition from skin essentially in an absence of human attendance. By the term “essentially” we stipulate that, although the system is configured to perform all actions related to the treatment per se in an absence of human attendance, presence of an operator is still required for inputting patient related data and/or spatially adjusting systems’ gear with regard to a patient and a skin surface area intended for treatment, accordingly. Presence of the operator is still highly desirable throughout the entire treatment for safety purposes.

[0060] The system, according to one aspect, is thus configured to combine and/or to synchronize system data comprising pre-determined and/or pre-selected system parameter settings, and patient-related data comprising parameter data related to the undesirable dermatological condition intended for treatment and obtainable prior to and throughout the treatment.

[0061] The system **100**, according to one basic embodiment, comprises a robot arm assembly **120** and a controlling unit **110** (FIG. 1). The robot arm assembly **120** comprises an articulated robot arm **102**, having an end effector configured as a laser head **101**. The laser head **101** is therefore coupled to the articulated robot arm **102**. The robot arm **102** is preferably implemented as a tabletop or otherwise an essentially small-sized robot arm manipulator having a number of segments interconnected by means of hinged joints to a kinematic chain. The height of the robot arm **102** when fully extended is about 500-1500 mm. In one exemplary embodiment (FIG. 2A) the robot arm **102** comprises a base **102a**, an upper arm **102b** supported at one end on the base **102a** by means of a shoulder hinge **103a** and a forearm **102c** pivoted to the other end of the upper arm **102b** by an elbow hinge **103b**. The forearm **102c** is further separated into two sub-segments by a rotary joint **103c** and comprises a rotatable joint adapter **104** at its free end configured to receive the laser head **101**. The rotatable joint adapter **104** thus forms a mounting means for the laser head **101**. The laser head **101** is mounted onto the forearm **102c** by means of aforesaid rotatable joint adapter **104**, accordingly.

[0062] The robot arm assembly **120** is preferably configured to have at least six degrees of freedom, indicated on FIG. 2B by roman numerals I-VI. In the assembly **120** shown on FIG. 2B the upper arm **102b**, supported on the base **102a**, is thus configured to rotate about its longitudinal axis (I) and to heave forward and backward (axis II) relative to the shoulder hinge **103a**, whereas the corresponding forearm **102c** is configured to perform the heaving motion relative the elbow hinge **103b** (axis III). The rotary joint **103c** further ensures rotational movement of a distal sub-segment of the forearm **103c** about its longitudinal axis (IV). By the distal sub-segment we refer to the sub-segment of the forearm **103c** connectable via the adapter **104** to the laser head **101**. The laser head **101** is further arranged to rotate about at least two orthogonal axes (herein V, VI) by means of the rotatable joint adapter **104**.

[0063] Aforementioned rotational axes are given by way of example, not limitation; therefore, the robot arm **102** and the assembly **120** may be embodied as having higher

degrees of freedom by implementing any or both of the robot arm segments **102b**, **102c** to extend telescopically, by providing different and/or additional rotational axes for joint connectors **103a-c** and **104** and/or by mounting the assembly **120** on tracks. Movements of the robot arm segments **102b**, **102c** and of the laser head **101** relative to each associated axis are realized by suitable motors, typically servo motors. The robot arm **102** may additionally comprise a variety of built-in sensors, such as torque-, pressure- and motion sensors, compensators, wire harnesses, cables and feeds, a power supply and any other components essential for the purposes of the present invention.

[0064] The system **100** according to another preferred embodiment is illustrated by FIG. 3, said system **100** further comprising a processing unit **111** implemented as a computer workstation, such as a tablet computer, a portable computer, a mobile electronic device and the like. The processing unit **111** may be further configured as a remote server workstation being in communication with the controlling unit **110** and/or the robot arm assembly **120** via wired and/or wireless connection. In the embodiment shown on FIG. 3 the controlling unit **110** and the processing unit **111** are provided as discrete devices interconnected by a number of wired and/or wireless communication lines (schematically shown by arrow). In some alternative embodiment the controlling unit **110** and the processing unit **111** may be combined within a single device.

[0065] The controlling unit **110** is implemented to execute direct controls over the robot arm assembly **120** and therefore comprises at least mechanical (motion) controllers for the robot arm **102**, laser function controllers for the laser head **101**, and a controlling means for integrating and coordinating functions of the laser head **101** with that of the robot arm **102**. The controlling unit **110** preferably comprises a laser source unit, power supply/supplies, motors, circuit boards, programmable logic controllers, control relays, drives, a cooling fan and a number of cable connectors/ports. The controlling unit **110** further comprises a front-panel control module (a user interface) and an associated circuitry. The front-panel control module may be realized as a graphical user interface (GUI) in the form of a display screen, preferably a touchscreen; as a control panel with a number of manual switches and an at least one monitoring panel/display screen; or as a combination thereof.

[0066] The controlling unit **110** is configured to communicate with the robot arm **102** via a communication line **105a**; and with the laser head **101**—via a communication line **105b** (FIG. 3). Said communication lines **105a**, **105b** are advantageously configured to comprise power transmission cables, connecting each of the robot arm **102** and the laser head **101** to the appropriate power source. The communication line **105a** further comprises a signal communication line provided in the form of a fiber optic cable, for example, and configured to transfer data on commands issued and/or mediated by the controlling unit **110** to the robot arm **102** for activating motion control mechanism(s) thereof and to receive feedback data, accordingly. The communication line **105b** further comprises a laser beam delivery system, configured to deliver laser beam from the power source (laser source), provided within the controlling unit **110** or separately therefrom, to the laser head **101**. The laser beam delivery system is advantageously configured as a fiber optic cable assembly, further comprising an input- and output

coupling optics and a number of connectors, adapters and the like. It is advantageous that one end of the fiber optic cable is permanently attached to the laser source whereas the opposite end of the cable includes a beam collimator and isolator enclosed into the laser head **101**.

[0067] The laser head **101** connected by means of the communication line **105b** to the laser source unit, advantageously provided within the controlling unit **110**, and the aforementioned laser source unit form a laser module within the system **100**. Selection of laser for the laser module is on one hand predetermined by an energy source (a pump source) and a gain medium, and on another hand, is object-related, i.e. dependent on the type of the undesirable dermatological condition intended for treatment, since successful treatment is largely anticipated by a wavelength of light emitted by laser.

[0068] In one preferred embodiment a Nd:YAG laser is utilized. The laser module is preferably configured as a Q-switched (QS) Nd:YAG laser capable of working in regimes of short pulses (in microsecond range) and/or ultra-short pulses (in nano- and picosecond ranges and shorter). Alternatively a Nd:YAG laser capable of producing light energy pulses in millisecond range may be utilized. In another preferred embodiment a so called frequency-doubled QS Nd:YAG laser, comprising, along with the Nd:YAG crystal, also a potassium titanyl phosphate (KTP) crystal, is utilized. While the common Nd:YAG lasers emit at 1064 nm (infrared), the aforesaid frequency doubled Nd:YAG lasers are capable of emitting at two wavelengths, namely, at 1064 nm and at 532 nm, wherein the latter wavelength (green) is produced by doubling the frequency of 1064 nm laser light by the KTP crystal. Laser emission at 1064 nm enables successful treatment of most frequently utilized dark tattoo pigments, such as black and dark-blue, whereas brown, red, orange, and some yellow pigments can be treated using the 532 nm wavelength. Moreover, since it is known that light absorption by epidermal melanin pigment at 1064 nm is less high than that at 694 nm produced by QS ruby laser and at 755 nm produced by QS alexandrite laser, utilization of QS Nd:YAG lasers reduces various skin alterations and/or scarring, especially upon treating patients with darker skin.

[0069] However, in order to treat other tattoo color formulations, such as green and blue, for example, additional and/or alternative utilization of other lasers, such as a QS Ruby laser emitting at the 694 nm and a QS Alexandrite laser emitting at the 755 nm, is not excluded.

[0070] Other important parameters to be determined and/or selected prior the treatment include laser power, intensity, fluence, pulse duration, pulse frequency, a number of pulses per a unit of time, as well as a spot size/diameter selected for treatment (in order to avoid treating surrounding unaffected area to minimize pigmentary alterations).

[0071] Reference is further made to FIG. 4 illustrating the laser head **101**. The laser head **101** thus comprises a casing **301**, having an aperture **302** for a lasing beam and a cable port **305** for receiving the communication line **105b**, which connects the laser head **101** to the laser source (provided within the controlling unit **110**, for example). Fixation of the laser head to the robot arm **102** and, in particular, to the joint adapter **104** thereof, is implemented by means of a fastening element **304**. Connections of the laser head **101** to the laser source and to the robot arm **102** mediated by the cable port **305** and the fastening element **304**, accordingly, can each be

either permanent or detachable. In some embodiment the laser head **101** is permanently connected to the laser source and detachably—to the robot arm.

[0072] The laser head **101** further comprises an at least one image acquisition device and an at least one proximity sensor. The image acquisition device is preferably a color camera utilizing CCD (semiconductor charge-coupled device), CMOS (complementary metal-oxide-semiconductor) or NMOS (N-type metal-oxide-semiconductor) technologies. The proximity sensor(s) may be any of the inductive, capacitive, photoelectric or ultrasonic sensors. Laser sensor(s) or ultrasonic sensor(s) may still be preferred. In the embodiment shown on FIG. 4 the camera and the proximity sensor(s) are provided within an appliance **303**. In some embodiment the sensor(s) may be integrated with the camera. The appliance **303** can be incorporated or fixed to the casing **301** or the fastening element **304**. Alternative configurations are possible (not shown), in which the camera and the proximity sensor(s) are disposed apart from each other.

[0073] In one preferred embodiment the laser head **101** comprises three proximity sensors, preferably solid-state sensors, located at a certain distance from each other to form a triangle. A “three-point” measurement implemented via the aforesaid configuration ensures correct alignment of the laser head **101** with respect to a predetermined point at skin surface area intended for treatment and allows to overcome errors caused by skin irregularity and degree of curvature.

[0074] Reference is further made to FIGS. 5A and 5B illustrating the system **100** according to some other embodiment. According to the embodiment shown on FIGS. 5A and 5B the system **100** further includes a treatment platform **201** for accommodating a patient **210** thereon (FIG. 5B). It should be noted that the system shown on FIGS. 5A and 5B may additionally include the processing unit **111** (not shown) either independently or as a part of the controlling unit **110**. The treatment platform **201** may further include auxiliary appliances (FIG. 5B), such as stairs **202** and/or wheels (not shown), whereas the robot arm assembly **120** may be further mounted onto a rack **203**. The embodiment of FIG. 5B shows a configuration, in which the rack **203** provides a support for both the robot arm assembly **120** and the controlling unit **110**. The rack **203** may further be rendered movable by provision of wheels **204**. Any other mounting means capable of providing sufficiently stable support for the robot arm assembly **120** and/or the controlling unit **110** may be alternatively utilized.

[0075] In some embodiment the treatment platform **201** may be provided separately from the rack **203**, therefore the rack **203** may be freely driven around the treatment platform **201**. In some other embodiments the treatment platform **201** and the rack **203** are attached to each other by means of guiding rails, for example, in order to enable sliding or rolling movement of the rack **203** along the edge of the treatment platform **201**. The guiding rails are advantageously provided with a locking means (not shown) in order to preclude accidental movements of the rack **203** during the treatment. The treatment platform **201** may, in turn, be implemented as a flat bed, an adjustable bed or a chair. An adjustable bed, with an at least one folding point in the middle and both ends being adjustable in vertical direction, is preferred. Such configuration is especially advantageous when the rack **203**, hosting the robot arm assembly **120**, is fixed to the treatment platform **201** by means of the above-

mentioned guiding rails, for example, since it allows treating either side of the patient's body (e.g. right and left arms) without disengaging the rack **203** and the treatment platform **201** from each other. Aforesaid configurations are given by way of example only; for those skilled in the art it is evident that other configurations, in view of design, realization and disposition of the treatment platform **201**, the rack **203** and the auxiliary appliances **202**, **204**, are possible.

[0076] The operation principle of the system **100** will be further described in more detail with reference to FIG. 6. The dotted-line box on FIG. 6 is herewith indicative of the system **100** being automated according to the definition above, i.e. defines a scope of actions executable by the system **100** throughout the treatment per se and in an absence of human attendance. For clarity purposes the treatment per se may be specified as a sequence of actions performed by the system **100** since a data on a skin surface area **501** intended for treatment and at least partly comprising an undesirable dermatological condition **410** has been input into the processing unit **111** or, in an absence of a distinct processing unit into the controlling unit **110** or a combination thereof, till the moment the robot arm assembly **120** has acquired a final position after having worked the entire area **501**.

[0077] Prior to the treatment an operator (a physician, a medical attendant etc.) switches on the system **100** and brings the robot arm assembly **120** into a sufficient proximity to the patient **210** and the undesirable dermatological condition **410** to be treated. As described above the robot arm assembly **120** may be mounted onto a movable rack further incorporating the controlling unit (not shown). The operator further defines the area **501** intended for treatment on patient's skin surface. The area **501** may be defined by drawing straight lines in x and y directions around or within the dermatological condition **410**, with or without a reference mark, and measuring length and width of a rectangular thus obtained. In the example shown on FIG. 6 the area **501** is therefore rectangular and entirely incorporates the condition **410**. In some particular instances the operator may define the shape of the area **501** as being other than rectangular, such as square, triangular, circular and the like, whether appropriate. Also more complex shapes are not excluded. In some other instances the area **501** may not necessarily incorporate the entire condition **410**; therefore, in case of large and very large dermatological conditions to be treated, such as large tattoos, for example, the operator may have to determine the area **501** within the dermatological condition **410**, in which case the area **501** includes the condition **410** only partly.

[0078] The operator further inputs measured parameters and other patient-related data into the processing unit **111**. Patient-related parameters may thus be selected from the group consisting of: dimensional parameters, such as length, width, diameter, radius etc., of the skin surface area **501** intended for treatment, skin color, type of the dermatological condition and a pigment color, whether the dermatological condition is tattoo. Mentioned parameters may be input manually or at least partly automatically, by means of photographing the dermatological condition **410** intended for treatment, for example. The operator further inputs and/or adjusts laser parameters, such as power, pulse duration, spot diameter, pulse frequency, a number of pulses per a unit of time, and optionally a wavelength. Further opera-

tional stages are advantageously performed by the system **100** in an operator-independent manner.

[0079] Based on the patient-related parameter data input into the processing unit **111** a virtual field model **502** is created. The model **502** constitutes a two-dimensional representation of the skin surface area **501**, whose boundaries are determined by virtual axes x and y, corresponding to length and width of the skin surface area **501**. Parameters for grid **503** formation are further determined. Upon grid formation the model **502** is split into a number of sub-areas **504**, preferably equal-sized, further referred to as squares. In one preferred embodiment the size of each sub-area **504** is 1 square inch (1"x1"). Dimensional calculations for each square **504** include the amount of spatial deviation intended to correct errors caused by skin surface irregularities and/or degree of curvature. In fact, each square **504** in the grid **503** comprises a border edge by which extent it overlaps with the neighboring squares. Dimensions of such overlapping edges ("joint seams") can be standardized or determined case-wise. In practice, width of the border edge around each individual square **504** may vary within a range of 10-25% with respect to the width of a single square, thus constituting 0.1-0.25 inch. The data on the field model **502** and the grid **503** is stored in the memory of the processing unit **111**.

[0080] Data on thus formed grid **503** is further communicated to the controlling unit **110** (not shown), in which said data is transformed to a number of commands for the robot arm assembly **120**. The robot arm assembly **120** is further configured, by means of the proximity sensors provided in the laser head **101**, to estimate a starting position of the laser head **101** with regards to the skin surface area **501** based on the virtual model **502** and the grid **503**. The skin surface area **501** intended for treatment may thus be considered as comprising a number of individual portions **501a**, each portion **501a** corresponding to a related virtual sub-area **504**. Determination of the starting position includes selection of a "first" virtual sub-area **504** and selection of a certain location therewithin (i.e. corner or center) and further acquisition of a starting point within the related skin portion **501a**, corresponding to said "first" sub-area **504**. As an exemplary first sub-area, indicative of a starting position hereby, a square at the lower left corner of the grid **503** may be selected (marked by a capital "S", FIG. 6). The starting position of the laser head **101** with regards to each subsequent virtual sub-area **504** and the related skin portion **501a**, accordingly, may be determined in the same manner.

[0081] Selection of a starting position within the virtual model **502** and selection of the directions along x and y axes for a "row-wise" movement of the robot arm **201** carrying the laser head **101** may be pre-programmed; however manual input, selection and/or modification thereof is preferably made available. The laser head **101** is then positioned such that lasing beam trajectory would form an essentially right angle with an imaginary line on the skin surface it falls onto. The term "essentially right angle" is used in the present disclosure to indicate an angle formed between a lasing beam and a skin surface being within a range of 60° to 90°. Acquisition of a starting point, i.e. of a point within the skin portion **501a**, corresponding to the "first" virtual sub-area **504** ("S"), and within each subsequent skin portion includes positioning of the laser head **101** with regard to each of said skin portions, implemented preferably by means of three distinct solid state proximity sensors, as disclosed above, in order to attain a "three-point" measurement. However, in

case the dermatological condition **410** is very small, such as a small tattoo located on a finger, for example, proximity measurement(s) may be omitted.

[0082] After the laser head **101** has been aligned with respect to the aforesaid starting point within the skin portion **501a** corresponding to the “first” virtual sub-area **504** (“S”), an image of said skin portion **501a** is acquired by means of the image acquisition device, such as a color camera, provided within the laser head **101**. Thus, each individual skin portion **501a** being captured at a time by the image acquisition device corresponds to a single virtual square **504** and constitutes 1 square inch (1"×1"). Upon capturing individual skin portions **501a** the image acquisition device is preferably adjusted to additionally include the abovementioned spatial deviation correction data.

[0083] Proximity measurement data obtained by the proximity sensor(s) and data on captured images obtained by the image acquisition device, such as a color camera, for each individual skin region **501a** are transmitted to the controlling unit **110** and/or the processing unit **111** for processing and reconstruction of the dermatological condition **410** within the virtual field model **502** and the grid **503**. During reconstruction it is preferably monitored to which extent the images obtained from each skin portion **501a** overlap with each other; the overlapping edges are further removed automatically by means of an appropriate computer program product, according to some further aspect of the invention.

[0084] Once reconstruction is complete the processing unit **111** is configured to issue a “START” command for initiating a series of actions performed by the robot arm assembly **120** and resulting in the removal of the dermatological condition **410** within the pre-defined skin surface area **501**. In particular, the robot arm **102** is set to the starting position (“S”) and laser supply from the laser source to the laser head **101** is initiated. The command(s) issued by the processing unit **111** are advantageously mediated by the controlling unit **110**. The system **100** is preferably configured to notify the personnel and the patient by a sound signal, for example, on its readiness for starting laser supply onto skin. Sound notification may be issued by the processing unit **111** and/or the controlling unit **110**, accordingly. In some embodiments the lasing beam delivery onto skin after issuing a notification may be initiated automatically, within a predetermined time period (e.g. 30 sec after notification). In some other embodiments the system **100** may be configured to request confirmation for the start, optionally password-protected.

[0085] Upon receiving the “START” command the robot arm assembly **120** acquires the starting position (“S”) and laser supply to the laser head **101** is therefore initiated. Directing of the lasing beam towards the dermatological condition **410** (FIG. 6) follows the same principles as described above with respect to proximity measurements and image capturing of the individual skin portions **501a**. Laser ablation is thus executed square-wise in accordance with proximity and image data obtained beforehand. FIG. 6 schematically illustrates an event of laser ablation occurring within the individual skin portion **501a**, provided herewith as a “projection” of the virtual sub-area **504** (black square), by means of the lasing beam **310** emitted by the laser head **101** (for clarity purposes the actual skin portion **501a** is omitted from the schematics of laser ablation visualization).

[0086] Throughout the laser-assisted treatment of the dermatological condition **410** conducted within each individual

skin portion **501a**, the proximity sensor(s) and/or the image acquisition device provided within the laser head **101** are configured to continuously execute real-time proximity measurements and/or to acquire digital images, accordingly, of skin surface within each skin portion **501a** with predetermined frequency and in predetermined timeframe. Thus obtained data is continuously transmitted to the controlling unit **110** and/or the processing unit **111** for real-time processing. During processing the parameters for the virtual field model **502** and the grid **503** are updated, adjusted and communicated back to the robot arm assembly **120** via the controlling unit **110** or directly. The robot arm assembly **120** is configured, in response to the updated command received from the controlling unit **110**, to adjust the position of the robot arm **102** and/or the laser head **101** with respect to the individual skin portion **501a** being treated. A feedback loop control over the robot arm assembly **120** is thus implemented.

[0087] The laser-assisted treatment of the dermatological condition **410** at least partly comprised within the boundaries of the pre-defined skin surface area **501** is completed when all individual skin portions **501a** defined within said area **501** have undergone laser ablation.

[0088] As a consequence of the above-described “square-wise” approach and continuous, real-time updating of the individual skin portions’ **501a** related parameters, the lasing beam can be directed throughout the dermatological condition **410** within the predetermined area **501** with an extremely high precision. The approach additionally allows for avoiding ablation of pigment-free skin surface areas.

[0089] According to some other embodiment the system **100** may be configured to proceed directly to the laser-assisted removal of the dermatological condition **410** having the steps of preliminary obtaining a series of parameters data for each individual skin portion **501a** via the proximity sensor(s) and the image acquisition device omitted from the laser-assisted treatment. In such an embodiment obtaining the parameter data from each individual skin portion **501a**, directing laser energy thereto and issuing a series of updated commands to the robot arm assembly **120** based on said parameter data is executed simultaneously for each individual skin portion **501a**.

[0090] Additionally or alternatively, the system **100** may require indicating, by a marker, for example, of an at least one reference point on patient’s skin. The reference point may thus be used for determination and/or acquisition of the starting point (“S”) as disclosed above, and for adjusting positional data during laser ablation within each individual skin portion **501a**.

[0091] The system **100** preferably comprises manual ON/OFF switch control(s) and PAUSE control(s) and/or an emergency ON/OFF switch control for the entire system **100** and/or each of the laser supply, the robot arm assembly **120**, the controlling unit **110** and the processing unit **111**.

[0092] An exemplary laser-assisted treatment executed by the system **100** is illustrated by FIG. 7, said treatment being a tattoo removal. Figure on the left shows the undesirable dermatological condition **410**, being a tattoo, prior to treatment, and figure on the right shows the same during the course of the treatment (60 seconds from the beginning). Size of the tattoo **410** being treated is about 2×3 cm. Based on FIG. 7 one can ascertain that, additional of being highly

precise, the laser-assisted tattoo removal executed by the system **100** is times faster when compared to that manually performed by the operator.

[0093] In another aspect of the invention a method for operating and real-time controlling the automated system **100** for laser-assisted removal of undesirable dermatological condition from patient's skin is provided. The method comprises at least the following steps:

[0094] a. Generating and storing a virtual two-dimensional model **502** of a pre-defined skin surface area **501** intended for treatment, identifying a number of sub-areas **504** within said model **502**, wherein each sub-area **504** corresponds to an individual skin portion **501a** within the boundaries of the pre-defined skin surface area **501** intended for treatment, and issuing a series of commands to the robot arm assembly **120** to acquire a starting position with respect to the surface area **501** intended for treatment.

[0095] b. For each individual skin portion **501a** obtaining a series of parameter data by means of an at least one proximity sensor and an image acquisition device provided within the laser head **101**.

[0096] c. Directing, via the laser head **101**, laser energy to each individual skin portion **501a**.

[0097] d. Based on the parameter data obtained at step (b) issuing a series of updated commands to each of the robot arm **102** and the laser head **101** continuously during executing step (c) for each individual skin portion **501a**.

[0098] e. Repeating steps (c) and (d) for each individual skin portion **501a** within the pre-defined skin surface area **501**.

[0099] In some embodiment the method is configured such that the steps (b), (c) and (d) are executed simultaneously within each individual skin portion **501a**.

[0100] In some further aspect a computer program product is provided, said computer program product being embodied in a non-transitory computer readable medium, comprising computer code for causing the computer to execute the method items of the previous aspect. A computer is advantageously the processing unit **111**, according to the definition hereinabove. A computer program, also referred to as a program, software, software application, or code, can be written in any form of programming language, including compiled or interpreted languages, and it can be provided in any form, including a standalone program, a module, a component, a subroutine or any other unit suitable for use in a computing environment. A computer program can be configured to be executed on one computer or on multiple computers at one site or distributed across multiple sites and interconnected by a wired or wireless communication network.

[0101] It is clear to a person skilled in the art that with the advancement of technology the basic ideas of the present invention are intended to cover various modifications and equivalent arrangements included in the spirit and the scope thereof. The invention and its embodiments are thus not limited to the examples described above; instead they may generally vary within the scope of the appended claims.

1. An automated system for laser-assisted removal of an undesirable dermatological condition from skin, which system comprises

- a robot arm assembly, comprising a laser head coupled to an articulated robot arm, and
- a controlling unit,

said system is configured to sequentially direct, via the laser head, laser energy to a number of pre-determined, individual portions of skin identified within the boundaries of a pre-defined skin surface area intended for treatment and at least partly comprising said undesirable dermatological condition,

wherein the controlling unit is configured to adjust positioning of the robot arm assembly with respect to each individual skin portion and directing laser energy thereto in real time,

said controlling unit is further configured to receive a series of parameter data obtainable from an at least one proximity sensor and an image acquisition device provided within the laser head and,

based on said parameter data, to issue a series of updated commands to each of the robot arm and the laser head continuously throughout the treatment.

2. The automated system of claim 1, further comprising a processing unit configured to generate and store a virtual model of the pre-defined skin surface area intended for treatment, to identify a number of sub-areas within said model, wherein each sub-area corresponds to the individual skin portion within the boundaries of the pre-defined skin surface area intended for treatment, and to communicate the data on thus identified sub-areas to the controlling unit and/or the robot arm assembly.

3. The automated system of claim 2, wherein the processing unit is further configured to update and adjust the stored model based on the series of parameter data received from the controlling unit and/or the robot arm assembly and to communicate thus updated and adjusted model data to the controlling unit and/or the robot arm assembly, wherein updating, adjusting and communicating the model data is executed in real time and continuously throughout the treatment.

4. The automated system of claim 2, in which the controlling unit is combined with the processing unit.

5. The automated system of claim 1, comprising within the laser head three proximity sensors disposed on a pre-determined distance from each other.

6. The automated system of claim 1, wherein the laser is a Nd:YAG laser.

7. The automated system of claim 1, further comprising a treatment platform for accommodating a patient.

8. The automated system of claim 2, wherein each sub-area identified within the virtual model and each related individual skin portion within the pre-defined skin surface area intended for treatment constitutes one square inch.

9. The automated system of claim 2, wherein dimensional calculations for each sub-area additionally include a pre-determined amount of spatial deviation for correcting errors caused by skin surface irregularities and/or degree of curvature thereof.

10. The automated system of claim 1, configured for laser-assisted removal of a tattoo.

11. The automated system of claim 1, configured for laser-assisted removal of the undesirable dermatological condition selected from the group consisting of: scars, birthmarks, moles, freckles, lentigines, solar lentigo and hyperpigmentation.

12. A method for operating an automated system for laser-assisted removal of an undesirable dermatological condition from skin, which system comprises a robot arm

assembly, comprising a laser head coupled to an articulated robot arm, a controlling unit and a processing unit, said method comprising:

- a. generating and storing a virtual two-dimensional model of a pre-defined skin surface area intended for treatment, identifying a number of sub-areas within said model, wherein each sub-area corresponds to an individual skin portion within the boundaries of the pre-defined skin surface area intended for treatment, and issuing a series of commands to the robot arm assembly to acquire a starting position with respect to the surface area intended for treatment;
- b. for each individual skin portion obtaining a series of parameter data by means of an at least one proximity sensor and an image acquisition device provided within the laser head;
- c. directing, via the laser head, laser energy to each individual skin portion;

- d. based on the parameter data obtained at the method item (b) issuing a series of updated commands to each of the robot arm and the laser head continuously during executing the method item (c) for each individual skin portion;
- e. repeating the method items (c) and (d) for each individual skin portion within the pre-defined skin surface area.

13. The method of claim **12**, wherein the method items (b), (c) and (d) are executed simultaneously within each individual skin portion.

14. A computer program product embodied in a non-transitory computer readable medium and comprising computer code for causing the computer to execute the method items of claim **12**.

* * * * *