WHAT IS CLAIMED IS:

~~1. An imaging and therapeutic delivery system comprising:~~

~~an imaging component comprising an imaging shaft having a proximal end and a distal end and an imaging transducer at the distal end of the shaft;~~

~~a needle component comprising a needle shaft having a distal end and a proximal end and a needle structure reciprocally disposed on or within the shaft;~~

~~wherein the distal end of the needle shaft is configured to removeably attach to the distal end of the imaging shaft so that the shafts may be brought together to lie side-by-side with their respective axes generally parallel.~~

~~2. A system as in claim 1 wherein:~~

~~the imaging transducer on the imaging shaft is pivotally attached at the distal end of the imaging shaft;~~

~~the distal end of the needle shaft is disposed proximally of the pivotally attached imaging transducer when the needle shaft is attached to the imaging shaft;~~

~~the needle structure in the needle shaft reciprocates distally along the axis of the needle shaft; and~~

~~the imaging transducer pivots away from the axis of the needle shaft when the needle shaft is attached to the imaging shaft.~~

~~3. A system as in claim 1 wherein the imaging component further comprises an imaging handle section attached to a proximal end of the imaging shaft and the needle component further comprises a needle handle section attached to a proximal end of the needle shaft, wherein the imaging handle section and needle handle section together form a complete handle when the needle shaft is attached to the imaging shaft.~~

~~4. A system as in claim 3 wherein the imaging handle section has an interior which holds circuitry configured to connect the imaging transducer with an external imaging display and the needle handle section including mechanisms for advancing the needle structure.~~

1~~5~~. A system for treating an anatomical feature in tissue, said system comprising:

a real-time display connected to a controller;

means for projecting and adjusting at least one of a treatment boundary and a safety boundary on the display;

a treatment probe having a deployable needle structure and an imaging transducer connectable to the controller and display; and

at least one servo drive motor on the treatment probe connected to the controller, wherein the controller is configured to drive the servo motor to position the needle structure to provide a treatment which covers the treatment boundary and which does not extend beyond the safety boundary.

26. A system as in claim 15 wherein the needle structure of the treatment probe comprises a needle and a plurality of tines advanceable from the needle in a distally diverging pattern.

37. A system as in claim 26 wherein the at least one servo motor comprises a first servo motor which drives the needle and a second servo motor which drives the plurality of tines.

48. A system as in claim 15 wherein the projecting means comprises a user interface configured to allow the user to virtually adjust a size and/or a position of the treatment and/or safety boundary on the display.

59. A system as in claim 48 wherein the interface is on the treatment probe.

6~~10~~. A system for treating an anatomical feature in tissue, said system comprising:

a microprocessor configured to generate and project virtual boundary lines defining a projected treatment and/or projected safety region on a real time image of the tissue;

a real time image display configured to display the real time image and the projected virtual boundary lines;

a treatment probe having a shaft, a handle, a needle structure deployable from the shaft, a slider configured to position the needle structure relative to the shaft and an imaging transducer, wherein the transducer is connectable to the microprocessor that further generates the real time image;

a stop structure positionable along a length of the handle of the treatment probe, wherein a position of the stop structure of the handle of the probe (1) controls at least one of a position and a size of the virtual boundary lines defining the treatment and/or safety region projected on the real time image display and (2) physically limits movement of the slider to control deployment of the needle structure from the shaft so that subsequent treatment of the tissue is within the projected treatment and/or safety region, wherein the stop structure is positionable independently of the position of the slider and needle structure.

7~~11~~. A system as in claim 6~~10~~ wherein the needle structure of the treatment probe comprises a needle and a plurality of tines advanceable from the needle in a distally diverging pattern and wherein the stop structure comprises a needle stop element and tine stop element.

8~~12~~. A system as in claim 7~~11~~ wherein the needle stop element at least partially controls the position of the treatment or safety region projected on the real time image display and the tine stop element at least partially controls the size of the treatment or safety region projected on the real time image display.

9~~13~~. A system as in claim ~~11~~ 7 further comprising a handle attached to a proximal end of the treatment probe and wherein the positionable stop structure comprises a needle stop housing.

10~~14~~. A system as in claim 9~~13~~ wherein axial translation of the needle stop housing in the handle controls the position of the treatment region and/or the safety region.

11~~15~~. A system as in claim 10~~14~~ further comprising a needle carriage coupled to a proximal end of the needle, wherein the needle carriage slides axially within the handle to advance the needle and wherein the carriage engages the needle stop housing to limit needle advancement.

1216. A system as in claim 1115 further comprising a tine stop mounted on the needle carriage.

1317. A system as in claim 1216 wherein axial transition of the tine stop controls the size of the treatment region and/or the safety region.

1418. A system as in claim 1317 further comprising a tine slide coupled to proximal end(s) of the tines, wherein the tine slide slides axially on the needle carriage to advance the tines from the needle and wherein the tine slide engages the tine stop to limit tine advancement.

1519. A system as in claim 1418 further comprising a rotatable knob on the needle stop, wherein said knob can be used to manually advance and retract the needle stop relative to the handle and wherein the knob is coupled to the tine stop so that rotation of the knob can advance and retract the tine stop on the needle carriage, whereby axial translation of the knob controls the position of the treatment and/or safety boundary projected on the display and rotation of the knob controls the size of the treatment and/or safety boundary projected on the display.

1620. A system as in claim 610 further comprising a controller connectable to the probe for delivering energy to the needle structure, wherein the system is configured to control the size of the projected treatment or safety region based upon both an energy level set by the controller and the position(s) of the stop element(s) which determine(s) the position of the needle structure.