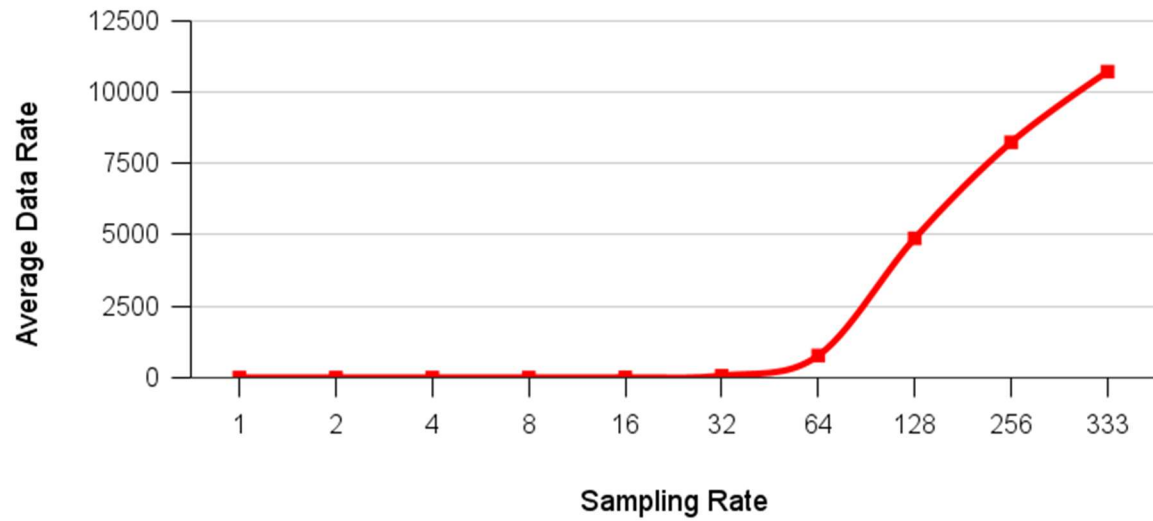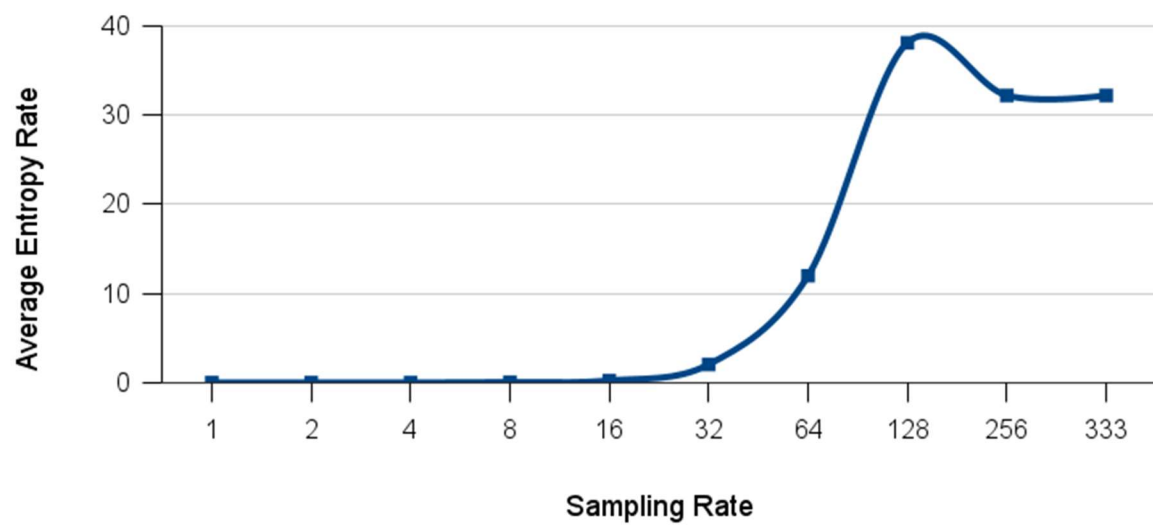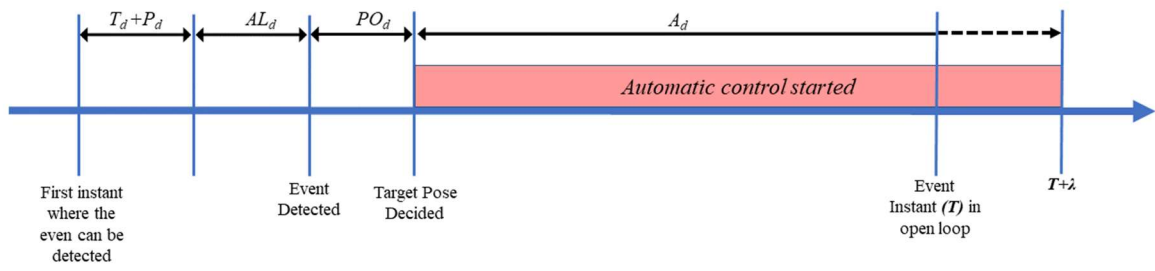**Fig 1**. *Illustration of the discrete end poses in Allegro Robotic Hand.*

Fig 2. Average data rate with respect to the sampling rate, when kinesthetic data of the robotic hand is modelled as a Markov Decision Process.
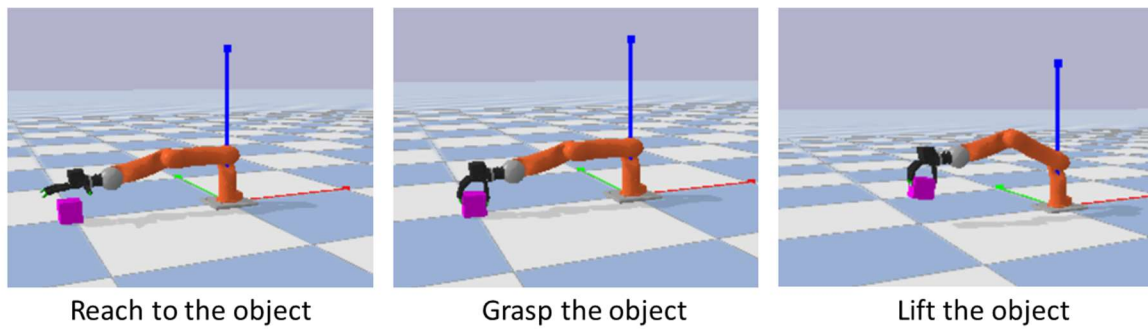

Fig 3. Average entropy rate with respect to the sampling rate, when kinesthetic data of the robotic hand is modelled as a Markov Decision Process.
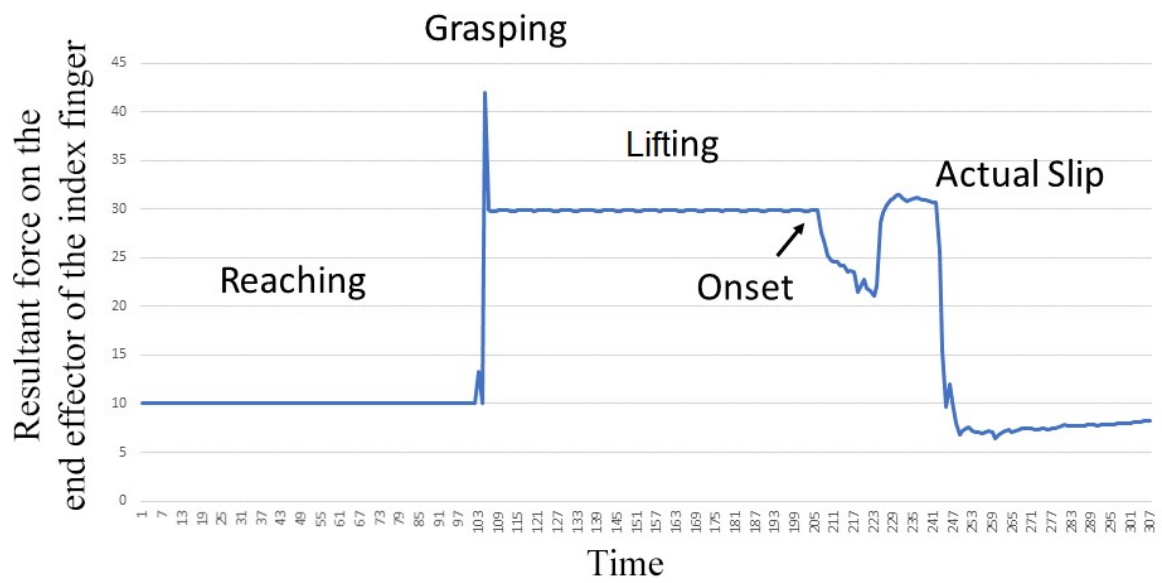
Fig 4. Timing diagram to represent the time-periods available for various actions in bilateral teleoperation.
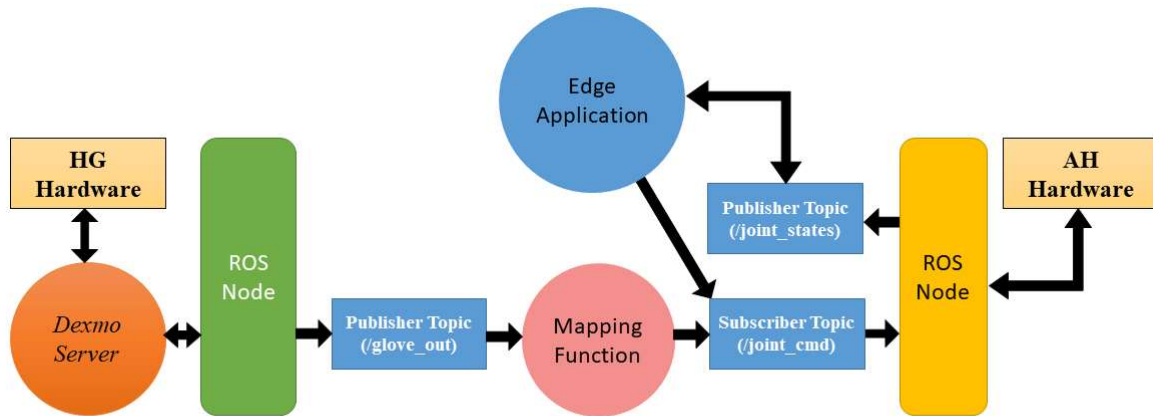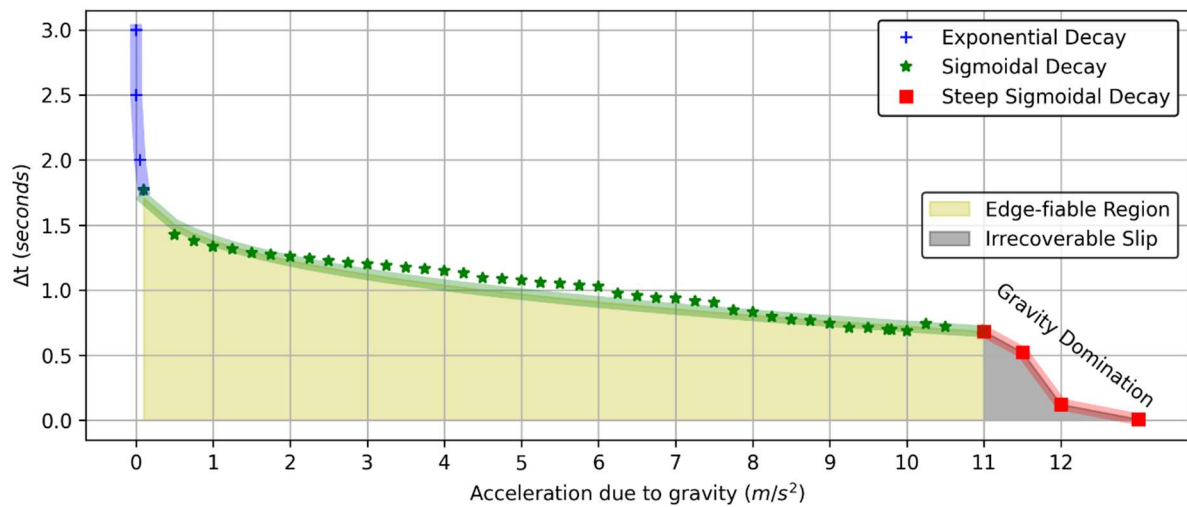

Fig 5. Setup of the system

Fig 6. Demonstration of various poses when picking up an object of interest.

Fig 7. Plot of kinesthetic feedback during various poses acquired while picking up an object of interest.

Fig 8. Edge-fiability analysis of logit based slip detection algorithm when deployed on edge.