1. **It's strange to have coefficient dimension as pixels/mm with default = 1 (3.2.3 Camera to image projection, formula 3.3) Why 1 pixel == 1 mm as default?**
   Corrected. The assumption is just that the pixels are squared, not that the scale is equal to 1.
2. **A division model was introduced by A.W. Fitzgibbon, so it's strange to have citation to Pritts et al., 2021 in this sentence: "A division model is very powerful and can express a wide range of distortions (Pritts et al., 2021)"**
   Added a reference to the origin. Pritts is cited because I re-used and expanded their approach to the inversion.
3. **"," and "." are often in the beginning of the line (after formulas)**
   Corrected.
4. **H from 3x3 matrix becomes 6-elements vector in "Now, by rewriting the equation in the matrix form M · H = 0, where H=(r__11, r__12, r__12, r__22, t__1, t__2)"**
   Changed the variable name to avoid confusion, and to correctly align with the notation.
5. **"To find t1 and t2, note that r1 and r2 are orthonormal" - they are orthonormal as 3d vectors, but one component is omitted. Do we suppose this?**
   That's a typo. I used symbolic math toolkit to verify my derivation, but used rows instead of columns to initialize the vectors. Actually, t_1 and t_2 are already found on the previous step, and now we're finding r_31 and r_32. Fixed.
6. **(4.12) and (4.32) seems to be absent formulas (or redundant label)**
   Corrected, thanks.
7. **Only the change to reprojection error was given as a camera calibration result. No comparison was made to classical camera calibration results and no discussion why results differ.**
   The main contribution of the paper is the recovery of the previously undetected features using an intermediate model (i.e. feature detection step). The obtained features can be used as an input to camera calibration toolchains, or the user can use the camera calibrations, provided by the proposed algorithm. However, we don't claim that the proposed camera calibration pipeline is better than the current SOTA.
   These newly found features will further constrain the camera calibration (also, typically it's the points near the edge of the image are not initially detected due to high distortion. These points contain more information about the camera parameters compared to the barely distorted points near the center of distortion).
   I added a clarification about that to the Metrics section, extended the description of the effect of additional points on the resulting camera calibration, and extended the description of the used metrics.
8. **In the following sentence I don't understand why the reference**

was made to section 5.7.3: "However, because of the occlusions, or similar to the board patterns in the background, there were false positives (section 5.7.3)."
Turns out, if the figure lacks a caption (as it was the case, only subfigures had ones), the reference to it breaks. Fixed.