

RESPONSE TO THE ASSOCIATE EDITOR'S COMMENT

We have removed appendix C and uploaded the code to a public depository:
Nguyen, D. H.: duchn7/circular_reel_out_controller: Initial release, Zenodo [code],
<https://doi.org/10.5281/zenodo.21775971>, 2026.

The code availability statement has also been updated accordingly:
“The simulation model is proprietary and is not available to the public. The Julia code for the flight controller can be downloaded from an online depository (Nguyen, 2026).”

The last sentence in the abstract that refers to the old appendix C has been removed.

RESPONSE TO REVIEWER 2'S COMMENTS

The three Euler angles on the reference plane are now explicitly defined on lines 166-167, reproduced below:

“From here, we obtain another set of Euler angles $[\phi_R, \theta_R, \psi_R]$ that depicts the kite's roll, pitch, and yaw angles with respect to the reference plane.”

We agree that using $\hat{\phi}$ or $\hat{r}$ to denote set points (e.g., ϕ_R^* or ϕ_R^r) can make the paper more readable than using ϕ_{RSP} . However, we prefer to retain the current notations to stay consistent with the code, which names variables such as ϕ_{RSP} as `phi_R_SP`.

Regarding the variable ϕ_{RPS} in the paper, this is indeed a typo from us. The correct name is ϕ_{RSP} as reviewer 2 has noted. We have corrected all instances of this issue in the latest version.

Regarding the computational aspect section, we agree with reviewer 2's judgement and have removed section 4.3.

Thank you again for the constructive comments from both reviewers and the associate editor.