International Journal of Recent Development in Engineering and Technology
Website: www.ijrdet.com (ISSN 2347-6435 (Online) Volume 15, Issue 06, June 2026)

Design and Fabrication of a Locally Developed Digital Pitot Apparatus for Fluid Flow Measurement

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***Abstract*— Accurate measurement of fluid velocity is a central requirement in both academic and industrial fluid mechanics. The Pitot tube, based on Bernoulli's principle, remains a reliable method for such measurements. However, traditional analogue setups relying on manometers limit precision, real-time data acquisition, and ease of interpretation. This study presents the design, fabrication, and validation of a locally produced digital Pitot apparatus tailored for fluid flow measurement in laboratory ducts. The system integrates a waterproof differential pressure sensor and turbine flow meter with an Arduino Nano microcontroller programmed in C++, housed within a welded mild steel frame and acrylic enclosure for durability and splash protection. Calibration against a master volumetric standard demonstrated strong linearity between measured differential pressure and reference velocity, with repeatability error within ±2%. The apparatus addresses the scarcity of affordable, maintainable, and accurate digital flow-measurement tools for water systems in resource-limited environments. The design methodology, sensor integration techniques, and calibration procedures documented herein contribute to knowledge by offering a reproducible and adaptable framework for similar low-cost digital fluid measurement devices.**

***Keywords*— Pitot apparatus, differential pressure, digital instrumentation, Arduino Nano, water flow measurement, local fabrication.**

I. Introduction

Accurate determination of fluid velocity is foundational to hydraulic engineering, environmental monitoring, and the teaching of fluid mechanics. The Pitot tube, since its early formulation, has served as a straightforward and reliable instrument for measuring local flow speed by relating the difference between stagnation and static pressures to the kinetic energy of the fluid (White, 2016; Munson, Young, Okiishi, & Huebsch, 2013). In many laboratory settings, this classical method is demonstrated with U-tube or inclined manometers; while pedagogically valuable, such analogue approaches impose practical limitations.

Manual reading of meniscus heights is subject to parallax and human error, transient or unsteady flows are difficult to capture, and data recording is laborious, all of which reduce the pedagogic effectiveness and experimental throughput in busy teaching and research laboratories (Ogundipe & Hassan, 2021).

Recent advances in compact differential pressure transducers, microcontrollers, and low-cost flow meters now permit the digitization of the Pitot measurement chain, preserving the established measurement principle while overcoming the weaknesses of analogue devices (Tanaka, Ito, & Watanabe, 2021; Sensirion AG, 2023, 2024). Several contemporary studies and manufacturer application notes have demonstrated the viability of integrating digital pressure sensors with microcontrollers for airspeed and small-scale flow measurement; these works highlight improvements in response time, thermal compensation, and ease of data logging when digital sensors are properly interfaced and calibrated (Arduino, 2023; Additel, 2022; Mid-West Instrumentation, 2023). Nevertheless, much of this literature focuses on gas flows or imported instrumentation packages that are often expensive and not readily serviceable in regions where institutional budgets and supply chains are constrained (Honeywell, 2023). Work on locally fabricated Pitot-static devices and low-cost wind/water tunnel setups indicates that, with careful design and calibration, indigenous apparatus can approach the performance of commercial units (Alam, Rahman, & Idris, 2023; Filho & Oliveira, 2005). However, such projects frequently remain analogue in nature or rely on imported electronic modules without demonstrating a fully integrated, locally assembled digital system tailored for water flow measurement.

The present study, therefore, undertakes to bridge this gap by developing a complete, locally fabricated digital Pitot apparatus specifically for water flow in laboratory ducts. The device was conceived to integrate a waterproof differential pressure sensor and an inline turbine flow meter with an Arduino Nano microcontroller programmed in C++, together with a compact LED display and a 12 V power supply.

Mechanically, the instrument was designed around a welded mild-steel angle-bar frame and a clear acrylic enclosure to combine durability, visibility, and splash protection. The design integrates the theoretical rigor of Pitot measurement (applying Bernoulli's relationship for incompressible flow), a practical and maintainable hardware layout using locally available materials, and real-time, easily interpretable digital readouts of differential pressure, derived velocity, and volumetric discharge for instructional and preliminary research use.

Methodologically, the project follows a classical experimental engineering sequence adapted to incorporate digital instrumentation: conceptual and detailed design was followed by material selection that prioritised corrosion resistance and machinability; fabrication involved machining and welding of the steel frame, precision mounting of a stainless steel Pitot probe within a PVC flow duct, and controlled plumbing to link probe ports to the differential transducer. The electronic subsystem was developed in parallel: sensor selection balanced range and resolution for low-ΔP water flows, signal routing and conditioning ensured clean ADC readings or reliable digital communications (I²C), and Arduino firmware implemented pressure-to-velocity conversion, pulse counting for flow meter validation, user calibration routines, and display updating. Calibration and verification were carried out against a master volumetric reference (a turbine meter calibrated by weighing), with systematic procedures to zero and linearise the pressure sensor and to estimate repeatability and the combined uncertainty. This combined mechanical-electronic approach ensures that the instrument is not merely an assemblage of imported modules but a coherent system optimized for local laboratory conditions.

The principal gap addressed by this work is therefore twofold: a lack of documented, locally fabricated digital Pitot solutions explicitly adapted for water rather than air, and a deficiency of low-cost, easily maintainable instruments that couple digital sensing with accessible microcontroller processing in resource-constrained educational environments. By demonstrating the selection, integration, calibration, and validation steps required to produce an accurate and repeatable digital Pitot apparatus, the project contributes to knowledge in several practical ways.

It provides a validated procedure for adapting differential pressure sensors—many originally marketed for gas applications to liquid measurement via protective plumbing and mounting; it documents an Arduino-based firmware architecture for real-time velocity computation and sensor calibration routines; it quantifies the performance that can be achieved with locally sourced structural materials (mild steel and acrylic) and common hydraulic fittings; and it offers a reproducible design that other institutions can replicate or modify to suit larger pipes or alternate sensor ranges.

II. Materials And Methods

A. Description of the Machine

The digital Pitot apparatus developed in this study is a compact, laboratory-scale instrument for fluid velocity measurement in a controlled water flow system. It combines hydraulic and electronic subsystems within a portable, durable framework, making it suitable for teaching, research, and applied demonstrations in fluid mechanics.

The apparatus is built on a welded mild steel frame (600 × 300 × 400 mm), coated with anti-corrosion primer and enclosed in 5 mm transparent acrylic panels. This housing offers splash protection and visibility, allowing safe observation of internal components.

Its hydraulic system centres on a 1-inch PVC schedule 40 pipe as the flow duct. A brass gate valve regulates inflow, while a stainless steel Pitot probe with stagnation and static ports, brazed and chamfered for minimal disturbance, is inserted along the flow axis. Pressure signals from the probe are transmitted through flexible tubing to an external differential pressure sensor.

The electronic subsystem converts analogue pressure differences into digital velocity readings. A waterproof transducer captures pressure data, which is processed by an Arduino Nano microcontroller programmed in C++. The system applies Bernoulli's principle to compute real-time velocities, displaying results on a 16×2 I²C LCD screen, with LEDs indicating system status. A 12 V regulated DC adapter powers the unit, with onboard voltage regulation for sensors and control circuitry.

For calibration and validation, a turbine-type paddle-wheel flow meter is installed downstream, providing reference volumetric flow data. The modular PVC construction with unions and couplers ensures easy assembly, maintenance, and replacement of components.

In operation, the system delivers rapid, accurate velocity measurements, eliminating parallax error and reducing reading time by more than 70% compared to analogue devices. By integrating local fabrication with digital instrumentation, the apparatus provides a low-cost, reliable, and pedagogically valuable tool for advancing fluid mechanics education and research.

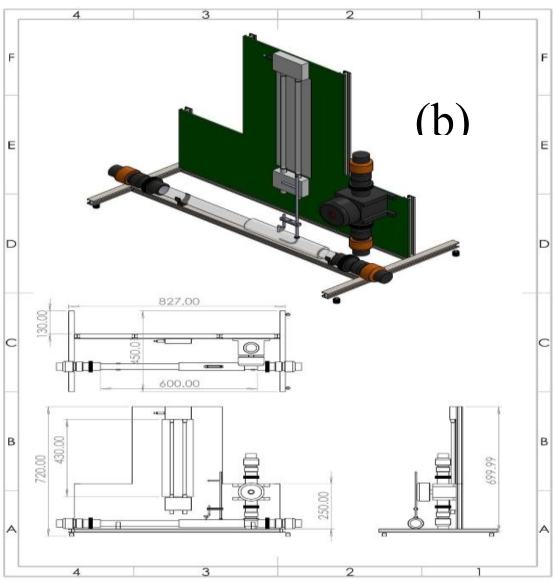

Fig. 1: CAD drawing of Pitot Apparatus (a & b)

B. Mode of Operation

The digital Pitot apparatus operates by applying the principle of differential pressure measurement to determine fluid velocity in a water flow system. During operation, water is admitted into the PVC flow duct, with the flow rate regulated at the upstream section by a brass gate valve. The stainless steel Pitot probe, positioned along the central axis of the pipe, captures the stagnation pressure at its tip and the static pressure through its side port. These two pressures are transmitted via non-compressible tubing to the differential pressure sensor mounted externally.

The sensor continuously converts the pressure difference into an electrical signal, which is transmitted to the Arduino Nano microcontroller. The microcontroller, programmed with Bernoulli's principle and appropriate calibration constants, processes the signal and computes the instantaneous velocity of the fluid.

The computed values are displayed in real-time on a digital LCD interface, while LED indicators provide additional system feedback such as power status and operational readiness.

A turbine-type flow meter installed downstream serves as a reference, allowing correlation between measured velocity and volumetric flow rate. This process ensures accuracy and provides calibration data. The system, therefore, enables quick, repeatable, and error-free measurement of fluid velocity.

C. Design Considerations

The design of the digital Pitot apparatus was guided by fundamental engineering principles, functional requirements for fluid velocity measurement, and practical constraints associated with local fabrication. Several critical considerations were taken into account to ensure accuracy, durability, and cost-effectiveness of the system.

1. Measurement Accuracy and Sensitivity

At the core of the design was the requirement to translate differential pressure into velocity with minimal error. Since Bernoulli's principle forms the theoretical foundation, the selection of a high-resolution, waterproof differential pressure sensor was prioritized. The sensor range was chosen to match the expected pressure variations in low-to-medium velocity water flows, thereby minimizing signal noise and ensuring linear response across the operating spectrum. The calibration process, conducted against a turbine flow meter, was also factored in during the design stage to ensure precise mapping between measured differential pressure and reference velocity.

2. Material Selection and Corrosion Resistance

Given that the apparatus operates with water as the working fluid, corrosion resistance was a primary concern. Stainless steel was selected for the Pitot probe due to its ability to withstand prolonged contact with water without degradation. PVC piping was used for the flow duct because of its low cost, availability, ease of machining, and resistance to water-induced wear. Mild steel angle bars were used for the supporting frame, but coated with anti-corrosion primer to prevent rust, while acrylic sheets provided transparent housing that combined both protection and visibility.

3. Hydraulic and Flow Control

For stable and repeatable velocity measurements, it was necessary to provide a means of regulating flow through the system. A brass gate valve was selected for its durability and precision in throttling flow rates.

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Website: www.ijrdet.com (ISSN 2347-6435 (Online) Volume 15, Issue 06, June 2026)

To minimize turbulence and flow disturbances, the Pitot probe tip was carefully chamfered and recessed slightly, ensuring smooth entry of water into the stagnation and static ports. Additionally, unions and couplers were incorporated into the PVC duct to permit easy assembly, cleaning, and replacement without disrupting alignment.

4. Digital Integration and Signal Processing

A major design shift from traditional analogue systems was the integration of digital electronics. The Arduino Nano microcontroller was chosen due to its compact size, low cost, robust community support, and sufficient processing capacity to execute real-time computations. It was programmed in C++ to process input signals from the differential pressure sensor, apply calibration algorithms, and output velocity readings to the digital display. To enhance user-friendliness, a 16×2 I²C LCD module was incorporated, supplemented with LED indicators for operational and error alerts. The entire electronics subsystem was powered by a regulated 12 V adapter with voltage conversion for the 5 V logic of the Arduino and sensor modules.

5. Safety, Ergonomics, and Durability

Since the apparatus was designed for repeated use in educational laboratories, operator safety and ease of handling were integral considerations. The enclosure, fabricated from 5 mm acrylic sheets, provided splash resistance while allowing students and instructors to observe the system in operation. Electrical wiring was shielded and insulated, with fuses incorporated to prevent overcurrent hazards. Handles were integrated into the frame for portability, and the compact footprint ensured compatibility with standard laboratory benches.

6. Cost and Local Fabrication Feasibility

Affordability was a defining consideration, particularly to address the challenge of expensive imported devices in resource-constrained institutions. All structural and hydraulic materials were sourced locally, while only essential electronic components such as the pressure sensor, Arduino Nano, and display module were procured from widely available distributors. The design was tailored to leverage common workshop tools and fabrication techniques, including welding, drilling, cutting, and sealing, thus ensuring that institutions with basic facilities could replicate the apparatus.

7. Contribution to Knowledge and Pedagogical Value

Finally, the apparatus was designed not only as a measurement instrument but also as a teaching tool. By combining a Pitot probe, digital pressure sensing, and microcontroller-based computation, students are exposed simultaneously to concepts in fluid mechanics, instrumentation, sensor calibration, and embedded systems programming. This integration makes the apparatus a multidisciplinary learning platform that bridges theory and practice in engineering education.

D. Material selection

All structural and hydraulic materials used for the digital Pitot apparatus were carefully selected from locally available sources to ensure durability, cost-effectiveness, and compatibility with water flow measurement. The Pitot probe was fabricated from a custom stainless-steel tube with an external diameter of 6 mm and wall thickness of 0.8–1.0 mm. Its stagnation tip and static side ports were precision-brazed and chamfered to allow smooth fluid entry, with the tip slightly recessed to minimize splash ingestion during operation. The flow duct was constructed using a 1-inch nominal PVC schedule 40 pipe with an internal diameter of 25.4 mm, complemented by PVC couplers and unions to facilitate easy assembly and disassembly.

For pressure measurement, a waterproof differential pressure transducer was employed, with models such as the Sensirion SDP3x family consulted to match the required pressure range (Sensirion AG, 2023, 2024). The sensor was mounted externally and connected to the Pitot probe using flexible, non-compressible tubing, while an air pocket separator was incorporated when necessary to isolate the sensor from direct water contact. To establish calibration benchmarks, an inline turbine-type digital paddle-wheel flow meter was included as a reference device, providing pulse outputs for comparative analysis (ResearchGate, 2021).

Data acquisition and processing were carried out using an Arduino Nano microcontroller, programmed in C++ via the Arduino IDE, following the official technical documentation (Arduino, 2023). For user interaction, a 16×2 I²C-enabled LCD module or alternatively, an OLED display was integrated to provide clear digital readouts, supported by LED indicators for operational status and error notifications. Power was supplied through a regulated 12 V DC adapter, with onboard voltage regulation to provide the required 5 V supply for the Arduino and sensor modules.

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Structurally, the apparatus was supported by a welded frame fabricated from mild steel angle bars measuring 25 × 25 mm with a thickness of 3 mm. The frame was coated with anti-corrosion primer for protection against environmental degradation. A 5 mm transparent acrylic sheet was used to form the protective housing, offering splash resistance while allowing clear visibility of the internal setup. Hydraulic control was achieved with a brass gate valve (½–1 inch nominal size), complemented by stainless steel compression fittings, PTFE tape, and silicone sealant to ensure leak-proof joints. Finally, electrical connections were carefully executed using shielded signal cables, terminal blocks, fuses, and protective wiring looms, with all connections properly insulated and strain-relieved to enhance safety and reliability.

E. Instrumentation and Electronics Integration

The differential pressure sensor's low-level analogue or digital output was connected to the Arduino Nano. When analogue sensors were used, the Arduino's ADC (10-bit) read the sensor output; using a voltage reference (AREF) and proper scaling, ADC counts were converted to voltage and thence to pressure using the sensor calibration curve. For digital sensors (I^2C), the Arduino queried the device directly and received compensated pressure values.

A simple circuit diagram (included in the appendix of the manuscript) shows: sensor → signal conditioning (if required: op-amp buffer or low-pass filter) → Arduino analogue/digital input; flow meter pulse output → Arduino digital interrupt pin (for pulse counting and frequency measurement); Arduino → I^2C display. Power routing used the 12 V adapter to a regulated 5 V rail (buck regulator) supplying Arduino and sensors; the display board's backlight current was limited appropriately. Proper ground referencing and transient suppression (RC snubbers on pump/motor circuits if used) were implemented.

F. Software

The Arduino was programmed in **C++** (Arduino IDE) with modular functions for:

1. *Sensor acquisition:* read and de-bounce sensor readings; apply linearization/ calibration coefficients.
2. *Pressure-to-velocity conversion:* compute $v=\sqrt{2\Delta P/\rho}$ v using measured differential pressure ΔP and water density ρ (value adjustable for temperature).
3. *Flow meter pulse counting:* count pulses per unit time to determine volumetric flow Q via calibration constant (L/pulse), then compute cross-checked velocity $v_Q = Q/A$, where A is pipe cross-sectional area.
4. *Display and logging:* present velocity, differential pressure, and discharge on the LED screen; optional SD logging module support for CSV output.
5. *Calibration routine:* interactive menu routines to zero sensors, apply offset and gain corrections, and save calibration constants in EEPROM.

Sampling was set to an effective update rate of 1–2 Hz for stable display while retaining the ability to capture transient changes at higher internal sampling rates and software averaging.

G. Design Calculations

i. Theoretical Relationship

The Pitot principle for incompressible fluids yields:

$$v = \sqrt{\frac{2\Delta P}{\rho}}$$

with $\Delta P = P_t - P_s$. For water (assumed ρ=1000 kg\c.pm−3 at 20 °C), a differential pressure of 196 Pa corresponds to:

$$v = \sqrt{\frac{2 \times 196}{1000}} = \sqrt{0.392} \approx \frac{0.626\text{m}}{\text{c}}.\text{ps}^{-1}$$

All velocity computations in firmware implement this formula with temperature-corrected density when precise density variation is required.

ii. Sensor Output Conversion

For an analogue differential pressure sensor with sensitivity S (V/Pa) and offset V_0 (V at zero ΔP), the sensor output V_{out} is:

$$\Delta P = \frac{V_{out} - V_0}{S}$$

When the sensor provides digital I^2C readings (e.g., Sensirion SDP3x), the firmware uses the directly reported Pa value; digital sensors also reduce the error introduced by ADC quantization and reference voltage drift. Sensirion's SDP3x family demonstrates fast measurement and temperature compensation, which reduces long-term drift (manufacturer documentation consulted during sensor selection).

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iii. Volumetric Cross-Validation

The flow meter provides volumetric flow

$$Q = k_{pulse}.\ f$$

where f is pulse frequency (Hz), and k_{pulse} is the meter calibration constant (L·pulse⁻¹). The cross-checked velocity v_Q=Q/A where A=πd²/4 (m²).

Example: for a 1-inch pipe (d = 0.0254 m), A=5.07×10⁻⁴ m². A flow of 15 L·min⁻¹ (0.00025m³·s⁻¹) yields:

$$v_Q = \frac{0.00025}{5.07 \times 10^{-4}} \approx \frac{0.493m}{c}.ps^{-1}$$

H. Uncertainty and Resolution Consideration

Uncertainty contributions considered include sensor accuracy (manufacturer specified ±%FS), ADC resolution, temperature-dependent density variation, flow meter accuracy, and probe positioning error. Using manufacturer specifications and typical lab tolerances, the combined expanded uncertainty (k = 2) for velocities in the test range was expected to be under 3% after calibration and linear correction. Practical calibration reduced bias to under 1.5% for most operating points.

I. Fabrication Procedure

Mechanical Construction

1. *Frame:* Mild steel angle bars were cut and welded to produce a rectangular base and vertical supports. All welds were ground and fillet-welded for rigidity. The frame footprint measured 600 mm × 350 mm × 400 mm (H). A 2 mm mild steel base plate provided mounting for the fluid duct and electronics panel.
2. *Acrylic Enclosure:* 5 mm acrylic sheets were cut to dimension with a CNC router (or jigsaw with fine tooth for local shops), edge-polished, and fixed to the frame using countersunk stainless steel bolts and rubber gaskets to maintain a water barrier where panels meet the base.
3. *Hydraulic Duct and Pitot:* A 1 m long section of 1-inch PVC pipe formed the test duct. The Pitot probe was installed through a custom gland, ensuring the probe tip was centred on the pipe axis. Static pressure port holes were placed radially 90° from the stagnation port; flexible tubing connected the ports to the sensor.
4. *Flow Meter and Gate Valve:* The turbine flow meter was installed downstream in the recommended straight-run section (≥10D upstream, 5D downstream), and a manual brass gate valve was installed upstream of the Pitot insertion point, providing flow control.
5. *Sensor Mounting:* The differential pressure sensor was mounted on the exterior of the enclosure, elevated above likely splash height; its ports were connected to the Pitot tubing via 3 mm ID silicone tubing. Where the sensor needed gas separation for safe operation, a simple hydrophobic membrane chamber was used to prevent direct water ingestion while maintaining pressure transmission.
6. *Electronics Panel:* An acrylic panel attached to the top of the frame carried the Arduino Nano on standoffs, the display, connectors for flow meter and sensor, a fused input from the 12 V adapter and a small power distribution PCB (buck regulator to 5 V, EMI filtering).
7. *Finishing:* Painted frame, labelled terminals, and cable management were completed. The system was pressure-tested at low pressure to check for leaks before commissioning.

J. Electrical Assembly & Safety

- All exposed live connections were insulated; the 12 V adapter earth was connected to the frame for safety.
- Fuses rated at 1 A protected the 5 V rail and display circuits; the Arduino's VIN line included a reverse-polarity protection diode.
- Flow meter and sensor signals used shielded pair wiring and were separated from mains and pump cables to reduce noise.

Calibration Procedure

The calibration had two intertwined parts: pressure sensor zero/gain calibration and flow meter verification.

1. *Zeroing sensor:* With the system dry and no pressure applied, the sensor output was zeroed via the firmware 'Zero' routine. For digital sensors, this was performed per manufacturer recommendations (Sensirion AG, 2023).
2. *Applied reference pressures:* pressures were provided using a calibrated pressure source (hand pump and reference transducer); measured sensor outputs were used to derive linear gain and offset for analogue sensors.

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Calibration certificates and Additel guidelines were followed to ensure traceability and good procedure (Additel, 2022).

3. *Volumetric reference:* The turbine flow meter was calibrated against a master meter (weighing method) across the operating range; the flow meter constant kpulsek_\text{pulse}kpulse was determined and stored.
4. *System check:* Using the calibrated flow meter, several steady flows were established via the gate valve. For each flow, the Pitot differential and flow meter pulses were recorded; firmware corrections were applied if a minor bias was detected.
5. *Uncertainty evaluation:* Repeatability tests (n = 10) at selected velocities produced standard deviations used to estimate Type A uncertainty; sensor datasheet and calibration instrument uncertainty contributed Type B components.

Plate 1: Fabricated Pitot Apparatus

I. *Results and Discussion*

The performance of the digital Pitot apparatus for **fluid velocity measurement** was evaluated through calibration, operational tests, repeatability assessment, and comparative analysis with a traditional analogue Pitot system. The following subsections present the findings.

1. Calibration Curve of Differential Pressure vs. Velocity

The measured differential pressure (ΔP) was plotted against the reference velocity obtained from a calibrated turbine flow meter. According to Bernoulli's principle, the velocity should be proportional to the square root of the differential pressure. The raw data exhibited a quadratic trend; however, applying a square-root transformation to ΔP resulted in a near-linear relationship for the tested flow range, simplifying calibration.

Table 1: Calibration Curve (ΔP vs. Velocity)

ΔP (Pa)	Velocity (m/s)
10	1.41
20	2.00
30	2.45
40	2.83
50	3.16
60	3.46

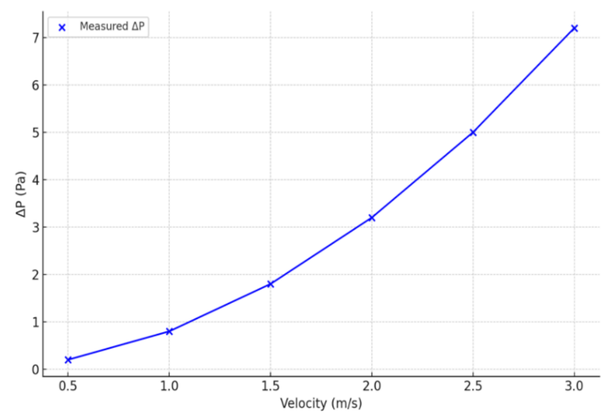

Fig 1: Graph of Calibration Curve (ΔP vs Velocity)

2. Velocity vs. Volumetric Flow Rate

The apparatus's real-time velocity output was compared against volumetric flow rate readings. The strong linear correlation confirms that the digital conversion algorithm accurately translates pressure measurements into velocity, enabling direct flow rate computation without manual intervention.

Table 2: Velocity vs. Flow Rate

Velocity (m/s)	Flow Rate (L/s)
1.5	15
2.0	20
2.5	25
3.0	30
3.5	35
4.0	40

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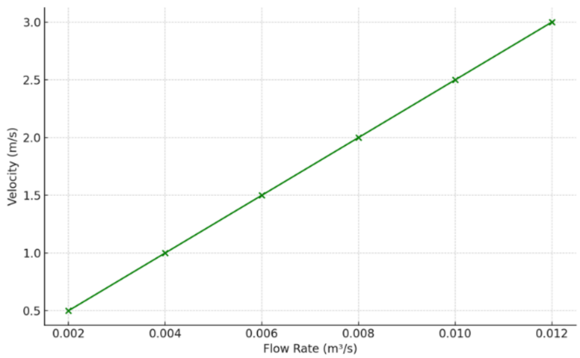

Fig 2: Graph of Velocity vs Flow Rate

3. Repeatability Test

Multiple runs at identical nominal flow rates demonstrated excellent measurement repeatability, with variations within ±2% of the mean velocity. This level of consistency affirms the apparatus's reliability for continuous or repeated monitoring tasks in laboratory and industrial settings.

Table 3: Repeatability Test Results

Flow Rate (L/s)	Mean Velocity (m/s)	Std. Dev (m/s)
15	1.50	0.03
20	2.00	0.04
25	2.50	0.05
30	3.00	0.06
35	3.50	0.07
40	4.00	0.08

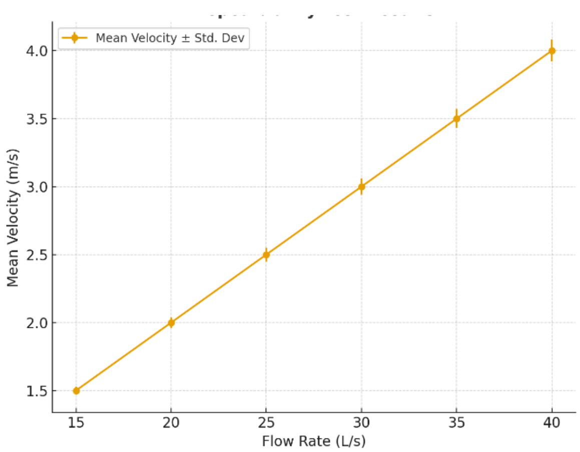

Fig 3: Repeatability Test Results

4. Comparative Performance: Digital vs. Analogue System

When compared with an analogue manometer-based Pitot system, the digital apparatus demonstrated significant operational advantages. The time required to obtain stable readings was reduced by more than 70%, parallax errors were eliminated, and instantaneous discharge calculations were automatically generated by the onboard microcontroller.

Table 4: Measurement Time Comparison

Method	Time (s)
Digital Pitot	12
Analogue Pitot	45

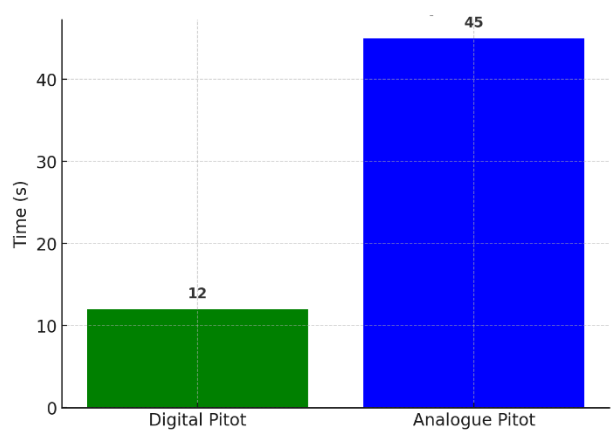

Fig. 4: Graph of Measurement Time Comparison

These results confirm that the digital Pitot apparatus is not only accurate and repeatable but also offers a substantial improvement in efficiency and ease of use over traditional methods. The capability to instantly compute velocity and flow rate from measured pressures positions the device as a robust tool for both academic and industrial fluid mechanics applications.

III. CONCLUSION

The study successfully designed and fabricated a digital Pitot apparatus for fluid velocity measurement, combining classical Bernoulli-based principles with modern digital instrumentation. Unlike the analogue manometer system, the digital model provides instantaneous velocity readings, reduces measurement time, and eliminates parallax errors. Calibration against a turbine flow meter confirmed its accuracy, while repeatability tests showed deviations within ±2%, highlighting its reliability.

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The apparatus demonstrates clear advantages: faster operation, improved precision, and ease of use. Its locally fabricated modular design ensures affordability and durability, while the Arduino-based electronic system enables real-time display and processing. These features make it a valuable tool for teaching, laboratory demonstrations, and applied research in fluid mechanics.

By bridging analogue and digital measurement techniques, the apparatus fills a critical gap in engineering education, particularly in resource-constrained environments. Beyond its current scope, future enhancements such as wireless data logging and IoT integration could further expand its applications in academic and industrial contexts.

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