

How to build an interleaved boost converter

PN173 | Posted on January 6, 2026 | Updated on February 18, 2026



Irati IBANEZ-HIDALGO

Project & Development Engineer

imperix • 

Table of Contents

- [Required hardware equipment](#)
 - [Passive components sizing](#)
- [Building and wiring the interleaved boost converter](#)
- [Analog input configuration](#)
- [Software](#)
 - [Creation of the Simulink model](#)
 - [Real time execution of the interleaved boost converter](#)
- [Going further](#)

This page is a quick-start guide to build an interleaved boost converter using imperix equipment. It is specifically made to accompany users who want to get familiar with imperix's solutions and build their first converter with the [B-Box 4](#) using the [Simulink](#) or [PLECS](#) blockset. The converter is built using imperix [power modules](#) and the [passive filter box](#).

The guide focuses on implementing an interleaved boost converter connected to a resistive load on the high-voltage side. The topology is shown in [Fig. 1](#). In this configuration, three legs are interleaved to reduce ripple and distribute current; nevertheless, the topology is scalable and additional legs can be incorporated if higher power requirements are needed. The basic working principles of a single-leg boost converter, which can be extended to the interleaved boost, are explained in [TN101](#).

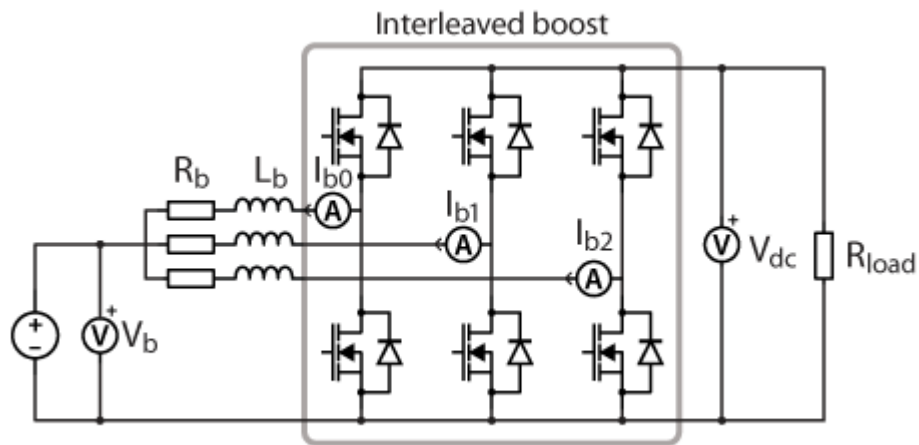


Figure 1. Schematic of the 3 phase inverter

This example is implemented using the B-Box 4 and PEB-800-40 power modules, but it can also be implemented using the B-Box RCP and other power modules. Detailed quick start guides for the B-Box 4 and the PEB-800-40 are available [here](#) and [here](#), respectively.

Required hardware equipment

The individual components required to build the interleaved boost converter are given below. The list comprises Imperix products as well as additional components commonly available in research laboratories:

- Imperix products:
 - 1x [programmable controller](#) (e.g. B-Box 4)
 - 3x [half-bridge modules](#)
 - 1x [passives filters box](#)
 - [Control development tools for Simulink and PLECS](#) (ACG SDK), with a valid license
 - 1x external [VSR-1000-ISO](#).
- Others:
 - 1x load resistor (see sizing below)
 - A DC power supply
 - Safety laboratory cables (banana)
 - Optional: voltage and current probes with an oscilloscope

Passive components sizing

The system uses a 500Ω resistor rated for 1.6A as the resistive load, which is compliant with the 700V DC bus voltage rating. This corresponds to about 1kW of power. If the user wishes to operate at higher power, a resistor with a higher power

rating should be used. More details regarding the sizing of passive components are given in [TN101](#).

Building and wiring the interleaved boost converter

The wiring of the system is executed as shown in [Fig. 2](#). The main points to consider are as follows:

- The Ethernet cable is connected to the back of the B-Box 4 so that it can be interfaced from Cockpit. More information on connecting to the controller is available in [PN138](#).
- Ensure each optical fiber is matched with its designated module and channel.
- The sensors are connected to the designated analog inputs of the controller. Further details on configuring the analog I/Os are provided in the next section.
- The midpoint of the modules is connected to the inductors.
- The DC source is correctly connected by linking DC+ to the outputs of the inductors, connected in star configuration, and DC- to VDC- of the modules (see [Fig. 2](#)).
- The DC buses of the modules are interconnected and connected to the external resistor.

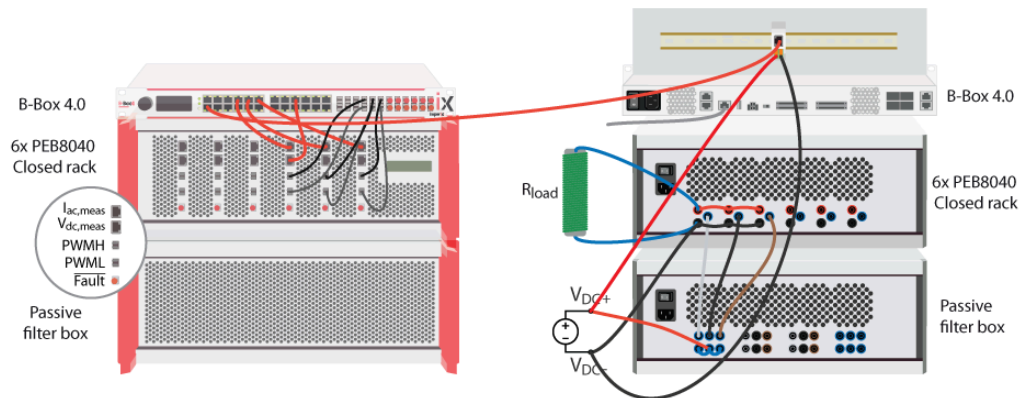


Figure 2. Interleaved boost converter wiring schema

Analog input configuration

This section focuses on the analog I/O configuration of the B-Box 4. More information about the analog I/O configuration for other imperix controllers can be found in [PN108](#).

Before doing any experiments, it is essential to properly configure the analog input channels of the B-Box 4. These channels have both hardware and software settings. The hardware settings can be configured from Cockpit or the B-Box 4 front panel, and the software settings are configured inside the Simulink or PLECS control model.

Software settings

- Channel number
- Sensor type
- Sensitivity and offset
- [Sampling strategy](#)

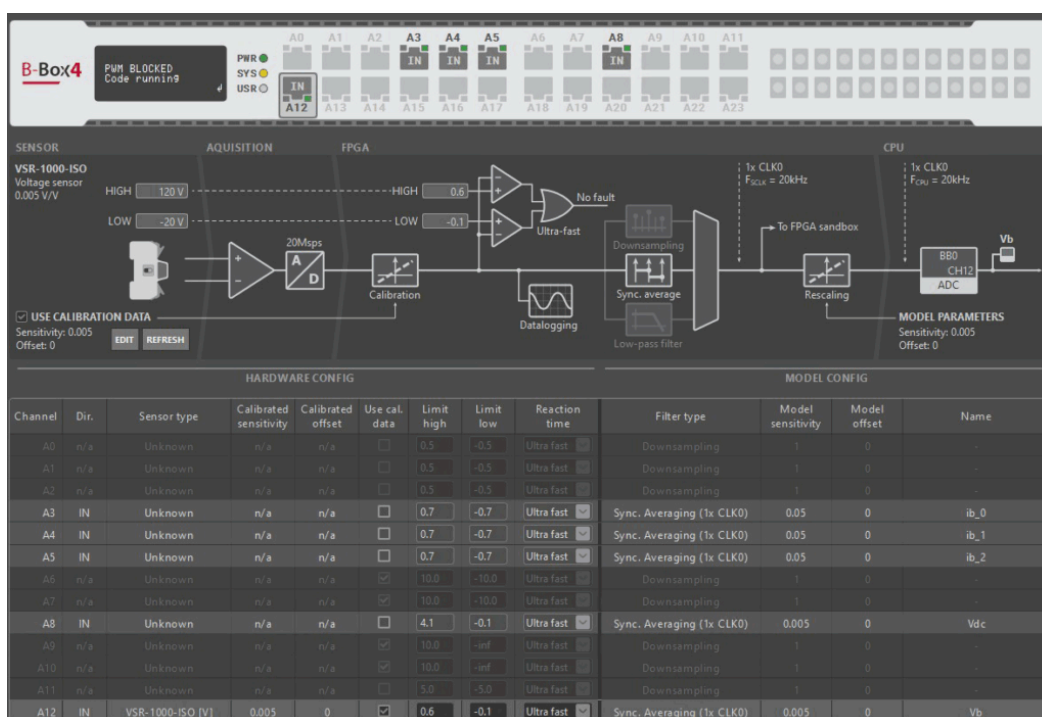
Hardware settings

- Protection reaction time (e.g. [over-current or over-voltage detection](#))
- Safety limits (upper and lower thresholds)
- For [auto-identified sensors](#): model parameters or sensor calibration data

More information about the ADC block of Simulink and PLECS blocksets can be found [here](#). Additionally, related information on the analog I/O configuration on B-Box 4 can be found in [PN252](#).

For the channel to which an external [VSR-1000-ISO](#) sensor is connected, the B-Box 4 automatically detects the sensor. The user can then choose to use the calibration data stored in the sensor's EEPROM. More information about sensor auto-configuration is provided in [PN255](#).

The analog channels have been configured as shown in [Fig. 3](#). The limits were computed with a safety margin to prevent undesirable tripping. In this case, no offset was detected. However, if an offset is observed on any channel (i.e., the measured value is different from zero when no signal is applied), the offset should be adjusted. This can be done through the [ADC block](#) or, for auto-identified sensors, via Cockpit. More information about sensor calibration is provided in document [PN255](#).



Software

Two pieces of software are required to develop the B-Box control code: the imperix [Automated Code Generation Software Development Kit](#) (ACG SDK), which can be downloaded [here](#); and a compatible version of [Matlab](#) (2016 and newer) or [PLECS](#).

A detailed guide on how to set up the software can be found in [PN133](#).

Creation of the Simulink model

The control model below implements open-loop output-current control, with step-by-step instructions for creating it provided afterwards. The implementation of a closed-loop current control is given in [PN171](#).

In this example, interleaved operation is used, meaning that the switching instant of each leg is shifted by $1/n$, where n is the total number of legs (in this case, three, resulting in a shift of $1/3$). This reduces the amplitude of the current ripple while simultaneously augmenting the apparent switching frequency (of the interleaved boost) by a factor of n .

To effectively reject the ripple in all three current measurements, [synchronous averaging](#) is applied to the ADC signals over exactly one PWM period. This automatically computes the averaged value of the individual currents, although the carriers – and hence current ripples – are phase-shifted. For reference, without oversampling, significantly more complex sampling strategies are required, notably such as presented in [TN122](#).

The open-loop model of the interleaved boost converter for Simulink and PLECS can be downloaded below. More information on how to create a Simulink or PLECS model are given in [PN134](#) and [PN136](#), respectively.

Simulink models

[PN173_InterleavedBoost_OL_SimulinkDownload](#)

PLECS models

[PN173_InterleavedBoost_OL_PLECSDownload](#)

Real time execution of the interleaved boost converter

Before performing any experiments, it is recommended to read the safety guidelines for working in the lab provided [here](#).

The code can be built by pressing Ctrl + B on Simulink (Ctrl + Alt + B on PLECS). This will automatically generate and compile the C code that will be uploaded to the B-Box 4. Pressing Ctrl + B also launches the Cockpit monitoring software. Additional details are available in the [Cockpit – User guide](#).

After [creating a new project and linking the user code with the controller](#), the user can set up the Cockpit workspace as in the following example:

- Two different scopes are added to the [scope module](#). The first one will include the three measured currents (I_{b_0} , I_{b_1} , I_{b_2}) and the second one the applied duty cycles (d_a , d_b , d_c).
- The DC bus voltage (V_{dc}) and the low-voltage side boost voltage (V_b) are added to a [rolling plot](#).
- The D variable is added to the [variables module](#).

Once the workspace has been set, the next steps can be followed to run the control software:

1. Make sure that PWM switching is disabled in Cockpit (project pane, upper-left in Cockpit), so that the converter remains inactive at first.
2. Gradually increase the DC supply voltage to 100V and check in Cockpit that V_b matches the DC source voltage. If it does not, check that the sensor is connected to the correct analog channel and that its sensitivity is properly configured. During this step, the DC bus will be precharged to approximately 100V.
3. Set the duty cycle variable D to 0.5. This corresponds to an output voltage V_{dc} that is twice the input voltage V_b , namely 200V.
4. Enable the PWM pulses in the inverter stage by toggling the PWM switching in the upper left corner of Cockpit. The DC bus voltage should rise to roughly 200 V. Due to the diode voltage drop and other non-idealities, it does not reach the theoretical value predicted by $V_{dc} = \frac{V_b}{1-D}$. A change in the duty cycle will result in a corresponding change in the DC bus voltage.
5. Verify that the boost currents I_{b_0} , I_{b_1} and I_{b_2} are constant currents with amplitude

$$I_b = \frac{V_b}{3R_{load}} \left(\frac{1}{1-D} \right)^2 (\approx 0.25 \text{ A}).$$

Since the current flows from the low-voltage side to the high-voltage side, it is considered negative. Thanks to the [oversampling](#) feature of the B-Box 4, by zooming in on the interleaved boost current scope, the current ripple can be observed, as well as the calculated average value of -0.25 A obtained after synchronous averaging. This is illustrated in [Fig. 4](#)

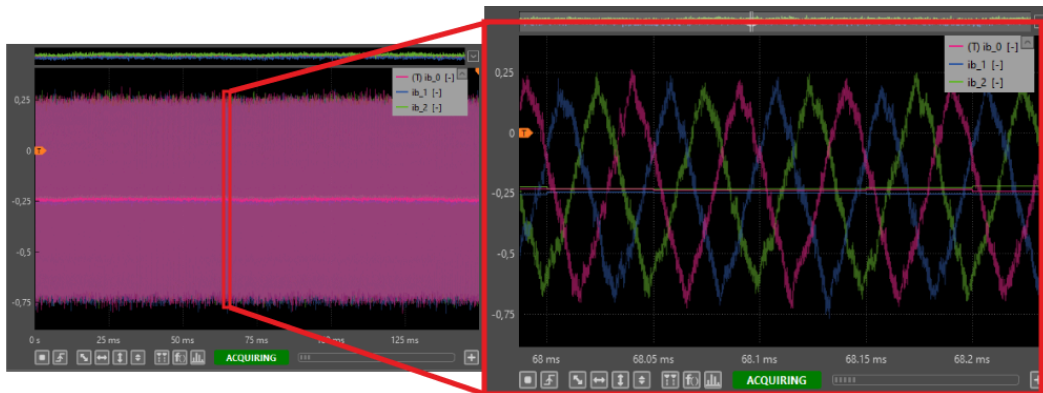


Figure 4. Oversampling measurement of the interleaved boost currents.

6. Gradually increase D to 0.86. The steady state results under these conditions are shown in [Fig. 5](#).

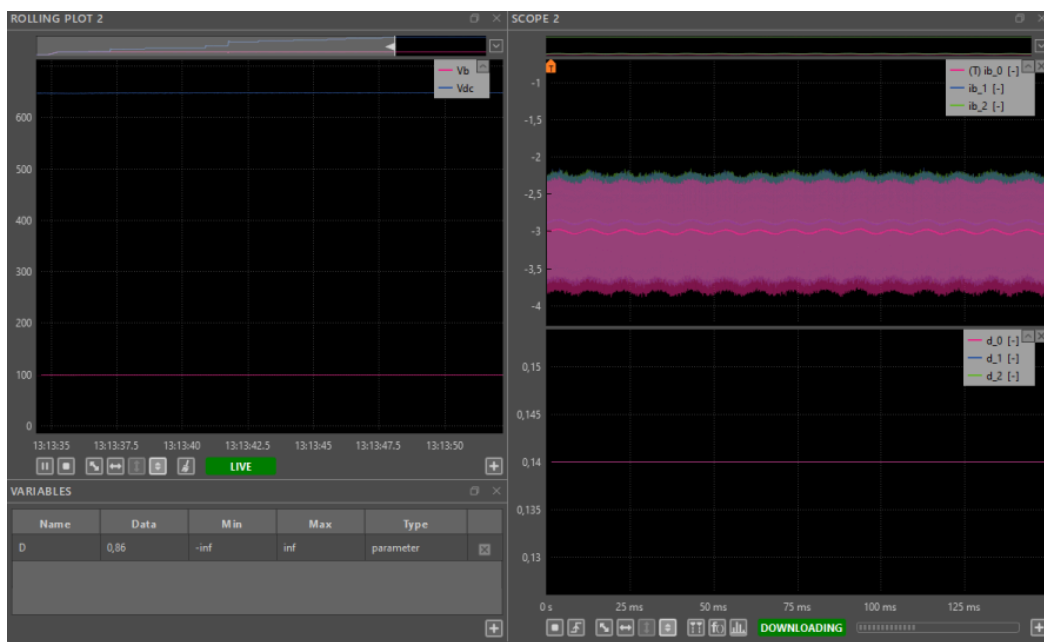


Figure 5. Cockpit workspace configuration and results of the experimental test.

7. Generate steps in the duty cycle by using the [transient generator](#) located in the right-hand panel. At $t=50\text{ms}$, D is modified from 0.45 to 0.6. This step will result in a higher DC bus voltage. In addition, as the required power increases during the transient and V_b keeps constant, the current through each leg of the interleaved boost will also increase. The obtained results can be observed in [Fig. 6](#).

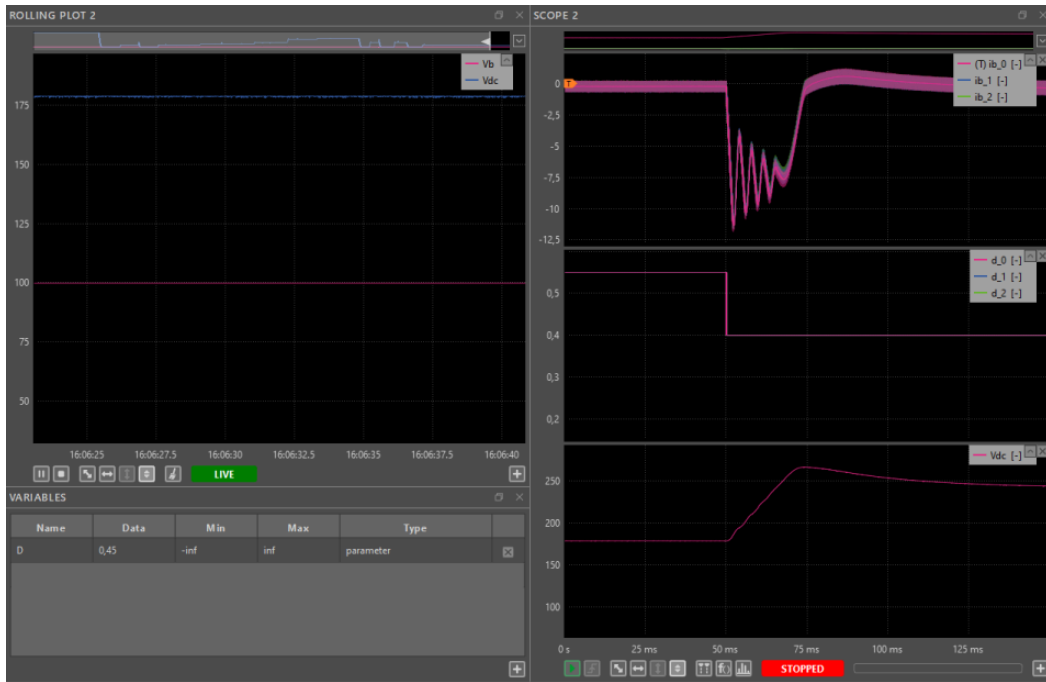


Figure 6. Results obtained after applying steps in the modulation index.

8. Deactivate the inverter by disabling the PWM pulses with the switch in Cockpit.
9. Decrease the DC supply voltage to 0 V and observe that Vb decreases to 0.

Going further

An alternative sampling configuration, for cases where synchronous averaging is not available, is presented in the [interleaved buck converter](#) note. On the other hand, for a more complex application where the interleaved boost is set in a back-to-back configuration with a three-phase inverter, the reader is redirected to [PN171](#).