

This work introduces a system for designing and evaluating experiments with evolutionary algorithms in 3D-simulated physical environments of the MuJoCo library. Experiments allow to develop the control and morphology of robots while using arbitrary user-defined fitness functions. The implementation was designed to be as accessible, understandable, and extendable as possible. The system offers a simple graphical user interface allowing a detailed configuration of experiments and a text-based user interface which is convenient for running large amounts of experiments for statistical analysis. The work implements several robots of different complexity, examples of various evolutionary algorithms, and a selection of well-known genetic operators. During experiment design, the architecture of this system allows the combining of implemented operators and tools arbitrarily. This work and the user documentation give simple instructions on how to alter and extend the implementation.