This work introduces a system for configuring and evaluating experiments with evolutionary algorithms in 3D simulated physical environments of the *MuJoCo* library. Experiments allow the development of the control and the morphology of robots while using arbitrary user defined fitness function. The implementation was designed to be as accessible, understandable and extandable as possible. The system offers simple graphical user interface allowing granular configuration of experiments and text-based user interface which is convenient for running large amounts of experiments for statistical analysis. The work implements a few robots of increasing difficulties some examples of different evolutionary algorithms and a selection of well-known genetic operators. While creating experiments the architecture of this system allows the creation of different combinations of all elements. This work together with the user documentation give simple instructions how to alter and extend the implementation.