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 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 granular configuration of experiments and a 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, 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 and the user documentation give simple instructions on how to alter and extend the implementation.