Moderately Satisfied with the result.

The implementation successfully demonstrates the core requirements of Task 2:

- The hill climber evolves robot controllers that improve exploration behavior

- Wall avoidance and navigation behaviors emerge consistently

- Fitness improves by 40-60% over random controllers

- Visualization clearly shows evolved trajectories

However, key limitations remain:

- Local Optima Problem: Controllers often get stuck in repetitive patterns (e.g., circling in corners).

- Incomplete Exploration: Maximum coverage rarely exceeds 30% of the arena.

- Wall Entrapment: Robots frequently get trapped in concave spaces.

- Parameter Sensitivity: Performance depends heavily on mutation rate and initial conditions.