CLAIMS

What is claimed is:

1. A method for controlling a virtual object, performed by an electronic device, wherein the method comprises:

obtaining a first operation instruction when a virtual object controlled by a client is performing an acceleration operation, wherein the first operation instruction is configured to instruct controlling the virtual object to perform a first target action;

determining whether the second operation instruction is obtained by the electronic device within a first target time period after the first target action is completed, wherein the second operation instruction is configured to instruct controlling the virtual object to perform a second target action;

adjusting movement of the virtual object from a first state to a second state, within a second target time period after the virtual object starts to perform the second target action, in a case that the second operation instruction is obtained by the electronic device within a first target time period after the first target action is completed, wherein a first power collected by the virtual object per unit time in the first state is less than a second power collected by the virtual object per unit time in the second state; and

adjusting an acceleration-control key corresponding to the acceleration operation to be in a state allowing touch control, in a case that the accumulating collected power reaches a trigger threshold;

wherein both the first target action and the second target action are drifting actions, and adjusting movement of the virtual object from the first state to the second state comprises at least one of:

increasing a virtual turning force applied on the virtual object, or

decreasing a virtual friction applied on the virtual object,

to increase a lateral speed of the virtual object,

wherein the virtual turning force points to a direction perpendicular to a forward direction of the virtual object, the virtual friction points opposite to an actual travelling direction of the virtual object, and the power collected by the virtual object per unit time increases with increasing of the lateral speed of the virtual object.

2. The method according to claim 1, wherein adjusting the movement of the virtual object from the first state to the second state within the second target time period after the virtual object starts to perform the second target action comprises:

obtaining a first value of a parameter, wherein the first value corresponds to a force applied on the virtual object in the first state; and

adjusting the first value of the parameter to a second value of the parameter, wherein the second value corresponds to the second state.

3. The method according to claim 2, wherein adjusting the first value of the parameter to the second value corresponding to the second state comprises:

increasing, based on a first target ratio, a first force-parameter value of the virtual object to a second force-parameter value, in a case that the applied force comprises the virtual turning force, wherein the first value of the parameter comprises the first force-parameter value, and the second value of the parameter comprises the second force-parameter value; and

decreasing, based on a second target ratio, a first friction-parameter value of the virtual object to a second friction-parameter value, in a case that the applied force comprises the virtual friction, wherein the first value of the parameter comprises the first friction-parameter value, and the second value of the parameter comprises the second friction-parameter value.

4. The method according to claim 2, wherein after adjusting the first value of the parameter to the second value corresponding to the second state, the method further comprises:

determining a lateral speed vector of the virtual object based on the second value of the parameter, wherein a direction of the lateral speed vector is perpendicular to a forward direction of the virtual object; and

obtaining the second power corresponding to the lateral speed vector.

5. The method according to claim 4, wherein obtaining the second power corresponding to the lateral speed vector comprises:

obtaining a square of a speed represented by the lateral speed vector; and

determining the second power based on a value of the square, wherein the second power is proportional to the value of the square.

6. The method according to any one of claims 1 to 5, wherein after adjusting the movement of the virtual object from the first state to the second state, the method further comprises:

obtaining a state of the virtual object performing the acceleration operation, in a case that duration of performing the second target action reaches a second threshold and a speed represented by the movement speed vector of the virtual object reaches a target threshold; and

displaying prompt information in the client, in a case that the state indicates that the virtual object is in an accelerating state, wherein the prompt information is configured to show that the virtual object has completed an action combination including the first target action and the second target action.

7. The method according to any one of claims 1 to 5, wherein the first target action and the second target action are the drifting actions toward to a same direction.

8. An apparatus for controlling a virtual object, comprising:

a first obtaining unit, configured to obtain a first operation instruction when a virtual object controlled by a client is performing an acceleration operation, wherein the first operation instruction is configured to instruct controlling the virtual object to perform a first target action;

a second obtaining unit, configured to determine whether the second operation instruction is obtained by the electronic device within a first target time period after the first target action is completed, wherein the second operation instruction is configured to instruct controlling the virtual object to perform a second target action;

a first control unit, configured to adjust movement of the virtual object from a first state to a second state, within a second target time period after the virtual object starts to perform the second target action, in a case that the second operation instruction is obtained by the electronic device within a first target time period after the first target action is completed, wherein a first power collected by the virtual object per unit time in the first state is less than a second power collected by the virtual object per unit time in the second state; and

a second control unit, configured to adjust an acceleration-control key corresponding to the acceleration operation to be in a state allowing touch control, in a case that the accumulating collected power reaches a trigger threshold;

wherein both the first target action and the second target action are drifting actions, and the first control unit is configured to perform at least one of:

increasing a virtual turning force applied on the virtual object, or

decreasing a virtual friction applied on the virtual object,

to increase a lateral speed of the virtual object,

wherein the virtual turning force points to a direction perpendicular to a forward direction of the virtual object, the virtual friction points opposite to an actual travelling direction of the virtual object, and the power collected by the virtual object per unit time increases with increasing of the lateral speed of the virtual object.

9. The apparatus according to claim 8, wherein the first control unit comprises:

a first obtaining module, configured to obtain a first value of a parameter, wherein the first value corresponds to a force applied on the virtual object in the first state; and

an adjustment module, configured to adjust the first value of the parameter to a second value of the parameter, wherein the second value corresponds to the second state.

10. The apparatus according to claim 9, wherein the adjustment module comprises:

a first adjustment sub-module, configured to increase, based on a first target ratio, a first force-parameter value of the virtual object to a second force-parameter value, in a case that the applied force comprises the virtual turning force, wherein the first value of the parameter comprises the first force-parameter value, and the second value of the parameter comprises the second force-parameter value; and

a second adjustment sub-module, configured to decrease, based on a second target ratio, a first friction-parameter value of the virtual object to a second friction-parameter value, in a case that the applied force comprises the virtual friction, wherein the first value of the parameter comprises the first friction-parameter value, and the second value of the parameter comprises the second friction-parameter value.

11. The apparatus according to claim 10, wherein the first control unit further comprises:

a determining module, configured to determine a lateral speed vector of the virtual object based on the second value of the parameter, wherein a direction of the lateral speed vector is perpendicular to a forward direction of the virtual object; and

a second obtaining module, configured to obtain the second power corresponding to the lateral speed vector.

12. The apparatus according to claim 11, wherein the second obtaining module comprises:

an obtaining sub-module, configured to obtain a square of a speed represented by the lateral speed vector; and

a determining sub-module, configured to determine the second power based on a value of the square, wherein the second power is proportional to the value of the square.

13. The apparatus according to any one of claims 8 to 12, further comprising:

a third obtaining unit, configured to obtain a state of the virtual object performing the acceleration operation, in a case that duration of performing the second target action reaches a second threshold and a speed represented by the movement speed vector of the virtual object reaches a target threshold; and

a display unit, configured to display prompt information in the client, in a case that the state indicates that the virtual object is in an accelerating state, wherein the prompt information is configured to show that the virtual object has completed an action combination including the first target action and the second target action.

14. The apparatus according to any one of claims 8 to 12, wherein the first target action and the second target action are the drifting actions toward to a same direction.

15. A storage medium, comprising a stored computer program, wherein:

the computer program when executed performs the method according to any one of claims 1 to 7.

16. An electronic device, comprising a memory and a processor, wherein:

the memory stores a computer program; and

the processor is configured to perform the method according to any one of claims 1 to 7 through the computer program.

17. A computer program product, comprising instructions, wherein:

the instructions, when executed on a computer, configure the computer to perform the method according to any one of claims 1 to 7.