CLAIMS

1. A method for virtual vehicle drifting in a virtual world, ~~performed by a terminal,~~ wherein the method comprises:

receiving, by a terminal, an event indicating a start of an operation corresponding to a widget for interacting with a target, during travelling of a virtual vehicle in the virtual world;

controlling, by the terminal, according to the event indicating the start of the operation, the virtual vehicle to be in a state of drifting in the virtual world;

monitoring, by the terminal, an angle between a direction pointed by a head of the virtual vehicle and a direction of the travelling; and

controlling, automatically by the terminal, the virtual vehicle to keep the state of drifting, in a case that ~~an~~ the angle ~~between a direction pointed by a head of the virtual vehicle and a direction of the travelling~~ is monitored to be greater than or equal to a first threshold, after an event indicating an end of the operation corresponding to the widget is received.

2. The method according to claim 1, wherein controlling the virtual vehicle to keep the state of drifting in the case that the angle is monitored to be greater than or equal to the first threshold comprises:

controlling the virtual vehicle to keep the state of drifting by controlling ground friction of the virtual vehicle in the case that the angle is monitored to be greater than or equal to the first threshold.

~~2~~3. The method according to claim ~~1~~2, wherein controlling the virtual vehicle to keep the state of drifting comprises:

applying a dynamic keep-drifting traction on the virtual vehicle along the direction pointed by the head of the virtual vehicle, wherein the dynamic keep-drifting traction is configured to control the virtual vehicle to keep the state of drifting.

~~3~~4. The method according to claim ~~2~~3, wherein magnitude of the dynamic keep-drifting traction is in positive correlation with a speed of the virtual vehicle within a preset range of the speed.

~~4~~5. The method according to claim ~~2~~3, further comprising:

changing the ground friction on the virtual vehicle from a first friction value to a second friction value, in a case that the angle between the direction pointed by the head of the virtual

vehicle and the direction of the travelling is greater than the first threshold, after the event indicating the end of the operation corresponding to the widget is received;

wherein the first friction value is greater than the second friction value.

~~5~~6. The method according to claim 1, further comprising:

increasing an attribute value for nitro of the virtual vehicle continuously, during the state of drifting;

activating a nitro-boosting widget of the virtual vehicle into an available state, in a case that the attribute value for nitro reaches a trigger threshold; and

controlling the virtual vehicle to accelerate, in a case that a signal triggering the nitro-boosting widget is received.

~~6~~7. The method according to any one of claims 1 to ~~5~~6, further comprising:

controlling the virtual vehicle to restore a state of normal traveling, in a case that the angle between the direction pointed by the head of the virtual vehicle and the direction of the travelling is less than the first threshold, during controlling the virtual vehicle to keep the state of drifting.

~~7~~8. The method according to claim ~~6~~7, wherein controlling the virtual vehicle to restore the state of normal traveling comprises:

switching the dynamic keep-drifting traction to traction for normal traveling;

wherein the traction for normal traveling is configured to control the virtual vehicle to be in the state of normal traveling; and

wherein the dynamic keep-drifting traction is greater than the traction for normal traveling.

~~8~~9. The method according to claim ~~6~~7, further comprising:

changing the ground friction on the virtual vehicle from a second friction value to a first friction value, in a case that the angle between the direction pointed by the head of the virtual vehicle and the direction of the travelling is detected to be less than the first threshold, during controlling the virtual vehicle to keep the state of drifting;

wherein the second friction value characterizes friction when the virtual vehicle keeping the state of drifting;

wherein the first friction value is greater than the second friction value.

~~9~~10. The method according to any one of claims 1 to 6~~5~~, further comprising:

receiving a steering operation;

changing the direction pointed by the head of the virtual vehicle according to the steering operation; and

determining an angle between the changed direction pointed by the head of the virtual vehicle and the direction of the travelling.

~~10~~11. The method according to any one of claims 1 to ~~5~~6, further comprising:

controlling the virtual vehicle to switch from the state of drifting to ~~the~~ a state of normal traveling after a target period, in a case that the direction pointed by the head of the virtual vehicle and the direction of the travelling is less than a second threshold, after the event indicating the end of the operation corresponding to the widget is received;

wherein the second threshold is less than the first threshold.

~~11~~12. The method according to claim ~~10~~11, wherein controlling the virtual vehicle to switch from the state of drifting to the state of normal traveling after the target period comprises:

calculating a decay period during which the virtual vehicle is turned from the state of drifting into the state of normal traveling, according to a velocity of the virtual vehicle and the ground friction;

controlling the virtual vehicle to be turned from the state of drifting into the state of normal traveling based on the decay period, in a case that the decay period is greater than a minimum drifting duration; and

controlling the virtual vehicle to be turned from the state of drifting into the normal traveling state based on the minimum drifting period, in a case that the decay period is less than the minimum drifting period.

~~12~~13. An apparatus for virtual vehicle drifting in a virtual world, comprising:

an interaction module, configured to receive an event indicating a start of an operation corresponding to a widget for interacting with a target, during travelling of a virtual vehicle in the virtual world; ~~and~~

a control module, configured to control, according to the event indicating the start of the operation, the virtual vehicle to be in the state of drifting in the virtual world; and

a monitor module, configured to monitor an angle between a direction pointed by a head of the virtual vehicle and a direction of the travelling;

wherein the control module is further configured to automatically control the virtual vehicle to keep the state of drifting, in a case that ~~an~~ the angle ~~between a direction pointed by a head of the virtual vehicle and a direction of the travelling~~ is monitored to be greater than or equal to a first threshold, after an event indicating an end of the operation corresponding to the widget is received.

14. The apparatus according to claim 13, wherein the control module is configured to control the virtual vehicle to keep the state of drifting by controlling ground friction of the virtual vehicle in the case that the angle is monitored to be greater than or equal to the first threshold.

~~13~~15. The apparatus according to claim ~~12~~14, wherein the control module is configured to:

apply a dynamic keep-drifting traction on the virtual vehicle along the direction pointed by the head of the virtual vehicle, in a case that the angle between the direction pointed by the head of the virtual vehicle and the direction of the travelling is greater than or equal to the first threshold, after the event indicating the end of the operation corresponding to the widget is received;

wherein the dynamic keep-drifting traction is configured to control the virtual vehicle to keep the state of drifting.

~~14~~16. The apparatus according to claim ~~12~~14, wherein the control module is further configured to:

change the ground friction on the virtual vehicle from a first friction value to a second friction value, in a case that the angle between the direction pointed by the head of the virtual vehicle and the direction of the travelling is greater than the first threshold, after the event indicating the end of the operation corresponding to the widget is received;

wherein the first friction value is greater than the second friction value.

~~15~~17. The apparatus according to claim ~~12~~14, wherein the control module is further configured to:

increase an attribute value for nitro of the virtual vehicle continuously during the state of drifting;

activate a nitro-boosting widget of the virtual vehicle into an available state in a case that the attribute value for nitro reaches a trigger threshold; and

control the virtual vehicle to accelerate in a case that a signal triggering the nitro-boosting widget is received.

~~16~~18. The apparatus according to any one of claims ~~12~~ 14 to ~~15~~17, wherein the control

module is further configured to:

control the virtual vehicle to restore a state of normal traveling, in a case that the angle between the direction pointed by the head of the virtual vehicle and the direction of the travelling is less than the first threshold, during controlling the virtual vehicle to keep the state of drifting.

~~17~~19. The apparatus according to claim ~~16~~18, wherein the control module is further configured to:

switch the dynamic keep-drifting traction to traction for normal traveling, wherein:

the traction for normal traveling is configured to control the virtual vehicle to be in the state of normal traveling; and

the dynamic keep-drifting traction is greater than the traction for normal traveling.

~~18~~20. The apparatus according to claim ~~16~~18, wherein the control module is further configured to:

change the ground friction on the virtual vehicle from a second friction value to a first friction value, in a case that the angle between the direction pointed by the head of the virtual vehicle and the direction of the travelling is less than the first threshold, during controlling the virtual vehicle to keep the state of drifting;

wherein the second friction value characterizes friction when the virtual vehicle keeping the state of drifting;

wherein the first friction value is greater than the second friction value.

~~19~~21. A terminal, comprising:

a processor, and

a memory,

wherein the memory stores computer-readable instructions, and the computer-readable instructions when executed by the processor configure the processor to perform the method according to any one of claims 1 to ~~5~~6, ~~7~~8, ~~8~~9 and ~~11~~12.

~~20~~22. A non-volatile computer-readable storage medium, storing computer-readable instructions, wherein:

the computer-readable instructions when executed by one or more processors configure the one or more processors to perform the method according to any one of claims 1 to ~~5~~6, ~~7~~8, ~~8~~ 9 and ~~11~~12.