Below is the assurance case for the BlueROV2 system (an underwater remotely operated vehicle) derived from the given assurance case pattern and displayed in a hierarchical tree format using dashes (-) to denote different levels:

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G1: Hazards for BlueROV2 system addressed in accordance with ALARP principle (undeveloped)

- S1: Argument by risk reduction/elimination of each hazard

- G2: No intolerable risks present in the system

- C1: Definition of "intolerable"

- S2: Argue that risk posed by any remaining hazards is negligible (undeveloped)

- S3: Argue that no other risks have been identified (undeveloped)

- G3: Risk from Deviation from the operating area has been reduced as low as reasonably practicable

- C2: Assigned severity class is Minor

- S4: Apply ReSonAte to estimate level of risk from hazard condition Deviation from the operating area

- A1: Function obstacle detection required by Avoidance Maneuver is available

- G4: Model Avoidance Maneuver accurately describes possible propagation of hazard Deviation from the operating area

- G6: Possible hazard propagation paths correctly captured in BTD (undeveloped)

- G7: Barriers in the BTD correctly describe their respective control action including any required system functions (undeveloped)

- G8: All non-negligible threats have been identified (undeveloped)

- G5: Quantitative risk estimates are accurate and below acceptable threshold

- G9: State probability distribution used for risk estimation is an accurate representation of expected system states (undeveloped)

- G10: Estimated probability of collision is below allowable threshold for severity class

- Sn1: Estimated risk level 10^-3 per hour

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This assurance case has been instantiated with specific details about the BlueROV2 system, such as the hazards, severity levels, functional models, and the BTD for the obstacle encounter hazard. Note that some elements remain undeveloped and would need further elaboration in a complete assurance case.