Here's an instantiated assurance case for the BlueROV2 system using the given assurance case pattern and the provided domain information. The instantiated placeholders are indicated within the descriptions.

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- Goal (G1, Hazards for BlueROV2 system addressed in accordance with ALARP principle.)

- Strategy (S1, Argument by risk reduction/elimination of each hazard)

- Goal (G2, No intolerable risks present in the system.)

- Context (C1, Definition of "intolerable")

- Strategy (S2, Argue that risk posed by any remaining hazards is negligible)

- Strategy (S3, Argue that no other risks have been identified)

- Goal (G3, Risk from obstacle encounter hazard has been reduced as low as reasonably practicable)

- Context (C2, Assigned severity class is Major)

- Strategy (S4, Apply ReSonAte to estimate level of risk from hazard condition obstacle encounter)

- Assumption (A1, Function avoidance logic required by obstacle encounter BTD is available)

- Goal (G4, Model obstacle encounter BTD accurately describes possible propagation of hazard obstacle encounter)

- Goal (G6, Possible hazard propagation paths correctly captured in BTD)

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

- Goal (G8, All non-negligible threats have been identified)

- Goal (G5, Quantitative risk estimates are accurate and below acceptable threshold)

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

- Goal (G10, Estimated probability of collision consequence is below allowable threshold for severity class)

- Solution (Sn1, Estimated risk level 10^-3 per hour)

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This hierarchical tree structure meets the given assurance case pattern, filling in specific details about the BlueROV2 system and its identified hazard ("obstacle encounter") along with its corresponding model and control strategies.

Key instantiations include:

- G1 refers to the overall goal of addressing hazards in the BlueROV2 system based on the ALARP principle.

- G3 specifically addresses the obstacle encounter hazard.

- C2 mentions the severity class of "Major" for the obstacle encounter.

- S4 involves estimating risk levels specifically for the obstacle encounter hazard.

- A1 states that function "avoidance logic" is required by the obstacle encounter BTD.

- G4 mentions that the obstacle encounter BTD accurately describes the hazard propagation.

Note that several elements (e.g., S2, S3, G6, G7, G8, G9) are marked as undeveloped according to the assurance pattern. These indicate that further development and detailing are required to fully develop the assurance case.