Here's the hierarchical tree format for an assurance case for the BlueROV2 system based on the provided pattern:

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

- 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) [Undeveloped]

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

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

- Context (C2, Assigned severity class is Major) [Uninstantiated]

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

- Assumption (A1, Function obstacle detection required by Avoidance Maneuver BTD is available) [Uninstantiated]

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

- 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) [Undeveloped]

- Goal (G10, Estimated probability of collision is below allowable threshold for severity class Major) [Uninstantiated, Undeveloped]

- Solution (Sn1, Estimated risk level 10^-3 per hour) [Uninstantiated, Undeveloped]

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

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

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

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This assurance case is aimed at demonstrating that the BlueROV2 system addresses hazards in accordance with the ALARP principle. Key components of this case include risk reduction strategies, probability estimation of consequences, and validation of functional and hazard models. Each instantiated element relates directly to specific aspects of the BlueROV2 system’s operation and safety measures. The placeholders, uninstantiated elements, and undeveloped nodes signify areas requiring further definition or evidence.