We have defined the following predicate rules for the elements and decorator used in an assurance case to ease understanding of an assurance case. The predicate rules for the elements and decorator of an assurance case begins with the delimiter *“@Predicate\_AC”* and ends with the delimiter *"@End\_Predicate\_AC”*

*@Predicate\_AC*

1. Goal(G): True if G is a goal within the assurance case. This predicate is represented as Goal (ID, Description) where ID is the unique identifier for the goal, and description is the textual information of the goal.
2. Strategy(S): True if S is a strategy within the assurance case. This predicate is represented as Strategy (ID, Description) where ID is the unique identifier for the strategy and description is the textual information of the Strategy.
3. Solution (Sn): True if Sn is evidence within the assurance case. This predicate is represented as Solution (ID, Description) where ID is the unique identifier for the evidence or solution and description is the textual information of the evidence.
4. Context(C): True if C is a context within the assurance case. This predicate is represented as Context (ID, Description) where ID is the unique identifier for the context and description is the textual information of the context.
5. Assumption (A): True if A is an assumption within the assurance case. This predicate is represented as Assumption (ID, Description) where ID is the unique identifier for the assumption and description is the textual information of the assumption.
6. Justification (J): True if J is a justification within the assurance case. This predicate is represented as Justification (ID, Description) where ID is the unique identifier for the justification and description is the textual information of the justification.
7. Undeveloped(X): True if X is either a Goal(G) or Strategy(S) marked as undeveloped. This predicate is represented as Undeveloped(X), where X can be either a goal or strategy.

*@End\_Predicate\_AC*

We have defined the following predicate rules for the additional decorators used to support assurance case patterns to ease understanding. The predicate rules for the additional decorators to support assurance case pattern begins with the delimiter *“@Predicate\_ACP”* and ends with the delimiter *"@End\_Predicate\_ACP”*

*@Predicate\_ACP*

1. Uninstantiated (X): True if element X (can be any GSN element) is marked as uninstantiated.
2. UndevelopStantiated (X): True if element X is either a Goal(G) or Strategy(S) and is marked both as uninstantiated and undeveloped.
3. HasPlaceholder (X): True if element ‘X’ (can be any GSN element) contains a placeholder ‘{}’ within its description that needs instantiation.
4. HasChoice (X, [Y], Label): True if an element ‘X’ (either a Goal(G) or Strategy(S)) can be supported by selecting among any number of elements in [Y] (where Y can be any GSN element) according to the cardinality specified by an optional Label. The label specifies the cardinality of the relationship between ‘X’ and ‘Y’. A label is of the general form “m of n” (e.g. a label given as “1 of 3” implies an element ‘X’ can be supported by any one of three possible supporting elements in [Y])
5. HasMultiplicity (X, [Y], Label): True if multiple instances of an element X (either a Goal(G) or Strategy(S)) relate to multiple instances of another element [Y] (where Y can be any GSN element) according to the cardinality specified by an optional Label. The label specifies the cardinality of the relationship between X and Y. (i.e., how many instances of an element in X relates with how many instances of an element in [Y]. e.g. m of n implies m instances of an element in X must be supported by n instances of an element in Y)
6. IsOptional (X, [Y], Label): True if an element X (either a Goal(G) or Strategy(S)) can be optionally supported by another element [Y] (where Y can be any GSN element) according to the cardinality specified by an optional Label. The label specifies the cardinality of the relationship between X and Y. (i.e. an instance of an element in X may be supported by another instance of an element in [Y], but it is not required)

*@End\_Predicate\_ACP*

To represent an assurance case or assurance case pattern in GSN is equivalent to depicting in a hierarchical tree structure. To achieve this hierarchical tree structure, the below predicates have been defined to ease understanding of this structure. The predicate rules to support the structure of an assurance case or assurance case pattern begins with the delimiter *“@Predicate\_Structure”* and ends with the delimiter *“@End\_Predicate\_Structure”*

*@Predicate\_Structure*

1. IncontextOf (X, [N], D): True if element X at depth D has a neighbour [N] to the left or right at depth D, where ‘[N]’ can be an Assumption (A), Justification (J), or Context (C), ‘X’ can be a Goal (G), or Strategy (S) and ‘D’ represents the height or depth of the goal or strategy element and its neighbours in the GSN hierarchical structure.
2. SupportedBy (X, [C], D): True if element X at depth D has children [C] directly below it, where [C] can include Goal (G), Strategy (S), or Solution (Sn) and ‘X’ can be a Goal (G), or Strategy (S).

* If X is Strategy (S), [C] can only be Goal (G).
* If X is Goal (G), [C] can be either Goal (G), Strategy(S), or Solution (Sn).

*@End\_Predicate\_Structure*

Now, I would provide you with domain information about the BlueROV2 system for which you would create an assurance case from a given assurance case pattern. The domain information begins with the delimiter *“@Domain\_Information”* and ends with the delimiter *“@End\_Domain\_Information”.*

*@Domain\_Information*

The BlueROV2 system is an advanced unmanned underwater vehicle (UUV) or underwater remotely operated vehicle (ROV). The main objective of the BlueROV2 system is to autonomously track pipelines on the seafloor while avoiding static obstacles such as plants and rocks or maintaining a safe distance from these obstacles and staying within designated operational boundaries ensuring safe and efficient underwater navigation.

Safety assurance for the BlueROV2 system is conducted through identification of potential hazards and reduction of the risk posed by those hazards based on the ALARP principle.

Like most modern Cyber Physical Systems (CPSs) which are highly complex and developed using Model

Based Engineering (MBE), the complete model set for the BlueROV2 System is comprised of many different DSMLs including BowTie, Functional, and Hazard models. These models aid in describing the system's functions, identifying hazards, and outlining hazard control strategies.

Three main potential hazards have been identified for the BlueROV2 system:

* Deviation from the operating area
* Obstacle encounter
* Loss of pipeline

For each hazard, a severity level is assigned based on any potential consequences that may result and an object describing the hazard exists in the hazard description model. For example, “the hazard Deviation from the operating area” has a severity level of “Minor”, “Loss of pipeline” has a severity level of “Minor”, “Obstacle encounter” has a severity level of “Major”.

Furthermore, each hazard also has an associated BTD which describes potential hazard escalation paths and control strategies. For example, the BTD describing the obstacle encounter hazard has “Avoidance Maneuver” and “Emergency Stop” barriers as control strategies implemented in the system. These strategies are critical for mitigating risks associated with the identified hazards.

Also, one functional decomposition model exists for each of three primary system functions: sensing, actuation, and control. Each of these models contain only a single function: obstacle detection, command authority, and avoidance logic respectively.

Finally, the obstacle encounter BTD contains one object of type “Consequence” which can be a “collision”,

with a risk estimate of 10^-3 per hour.

*@End\_Domain\_Information*