To create an assurance case for the BlueROV2 system using the given assurance case pattern and based on the template, we need to replace the placeholders with specifics about the BlueROV2 system and instantiate the assurance case. Additionally, decorators such as Uninstantiated must be removed, and undeveloped elements should be avoided or identified for future development. Here is the instantiated assurance case presented in a hierarchical tree format:

```

G1: Hazards for BlueROV2 addressed in accordance with ALARP principle.

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 operational hazards has been reduced as low as reasonably practicable.

- C2: Assigned severity class is high

S4: Apply ReSonAte to estimate level of risk from operational hazard.

- A1: Functionality for emergency shut-down is available

G4: Model of event tree accurately describes possible propagation of operational hazard.

G6: Possible hazard propagation paths correctly captured in event tree (Undeveloped)

G7: Barriers in the event tree correctly describe their respective control action including any required system functions (Undeveloped)

G8: All non-negligible operational 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 major system failure is below allowable threshold for high severity class.

- Sn1: Estimated risk level of less than 0.01% for major system failure

```

In this instantiation:

- \*\*Placeholders\*\* like `{A::System}`, `{B::Hazard}`, `{S::BTD}`, `{R::Hazard}`, `{U::Consequence}`, `{V::attr:RiskEst}`, `{T: Function}`, and `{C::Hazard.Severity}` have been replaced with specific terms relevant to the BlueROV2 system, indicating specific hazards, consequences, functions, and details about the system's BTD (Bow-Tie Diagram) and risk estimations.

- \*\*Contexts\*\* like "intolerable" and severity class definitions have been added directly related to G2 and G3 to inform the limits of these goals.

- \*\*Assumptions\*\* are made clear such as the availability of essential functions like emergency shut-down.

- \*\*Solutions\*\* such as estimated risk levels provide evidence supporting the claim that risks are below the defined thresholds.

- \*\*Undeveloped elements\*\* are noted, which will need further elaboration as part of the system's ongoing safety analysis and documentation.

- \*\*Uninstantiated decorators\*\* and placeholders have been removed, and the assurance case has been tailored specifically to BlueROV2.