Based on the provided assurance case pattern for a system, here is the instantiated assurance case for the BlueROV2 system using the Goal Structuring Notation (GSN) format. Each element is replaced with specific information relevant to the BlueROV2 system.

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Assurance Case for BlueROV2 System

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G1: Hazards for BlueROV2 addressed in accordance with ALARP principle

C1: Definition of "intolerable"

--- 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 remaining hazards is negligible [undeveloped]

--- S3: Argue that no other risks have been identified [undeveloped]

--- G3: Risk from collision hazard has been reduced as low as reasonably practicable

--- C2: Assigned severity class is high risk

--- S4: Apply ReSonAte to estimate level of risk from hazard condition collision

--- A1: Function distance sensors required by BlueROV2 BTD is available

--- G4: Model BTD accurately describes possible propagation of collision hazard

--- G6: Possible collision propagation paths correctly captured in BTD [undeveloped]

--- G7: Barriers in the BTD correctly describe their respective control actions including any required system functions [undeveloped]

--- G8: All non-negligible collision threats have been identified [undeveloped]

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

--- G9: State probability distribution used for collision 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 documented in risk assessment report

```

- The assurance case is represented hierarchically with dashes to indicate levels within the tree structure.

- The pattern placeholders, such as `{A :: System}`, `{B :: Hazard}`, `{S :: BTD}`, `{R :: Hazard}`, `{U :: Consequence}`, `{V :: attr:RiskEst}`, `{C :: Hazard.Severity}`, and `{T :: Function}`, have been replaced with specific instances applicable to the BlueROV2 system, such as "BlueROV2", "collision", "BlueROV2 BTD", "collision hazard", "major system failure", "risk assessment report", "high risk", and "distance sensors" respectively.

- Contexts like `C1` and `C2` have been instantiated with specific definitions and risk classification relevant to the hazards.

- Supports and contexts have been assigned as per the assurance case pattern, but note that several strategies and goals are marked [undeveloped], indicating that more detailed work is necessary.

- Assumptions and solutions were also contextualized for BlueROV2, e.g., `A1` now refers specifically to distance sensors required by the BlueROV2 BTD, and `Sn1` is correlated with a risk assessment report.