Based on the given assurance case pattern and the domain information provided about the BlueROV2 system, we can create an assurance case for BlueROV2. Here is the hierarchical tree format representation:

```

- G1: Hazards for BlueROV2 system addressed in accordance with ALARP principle. (undeveloped)

- S1: Argument by risk reduction/elimination of each hazard

- G2: No intolerable risks present in the system (undeveloped)

- 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 Deviation from operating area hazard has been reduced as low as reasonably practicable

- C2: Assigned severity class is Minor

- S4: Apply ReSonAte to estimate level of risk from hazard condition Deviation from operating area

- A1: Function Command Authority required by Avoidance Maneuver is available

- G4: Model Avoidance Maneuver BTD accurately describes possible propagation of Deviation from operating area hazard (undeveloped)

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

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

- G8, All non-negligible 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 collision is below allowable threshold for severity class (undeveloped)

- Sn1: Estimated risk level <10^-3 per hour>

- G3: Risk from Loss of pipeline hazard has been reduced as low as reasonably practicable

- C2: Assigned severity class is Minor

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

- A1: Function Command Authority required by Emergency Stop is available

- G4: Model Emergency Stop BTD accurately describes possible propagation of Loss of pipeline hazard (undeveloped)

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

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

- G8, All non-negligible 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 collision is below allowable threshold for severity class (undeveloped)

- Sn1: Estimated risk level <10^-3 per hour>

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

- C2: Assigned severity class is Major

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

- A1: Function Obstacle Detection required by Avoidance Maneuver is available

- G4: Model Avoidance Maneuver BTD accurately describes possible propagation of Obstacle encounter hazard (undeveloped)

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

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

- G8, All non-negligible 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 collision is below allowable threshold for severity class (undeveloped)

- Sn1: Estimated risk level <10^-3 per hour>

```

Explanation of the created assurance case:

- The top-level goal (G1) asserts that hazards for the BlueROV2 system have been addressed in accordance with the ALARP principle.

- The strategy (S1) supports G1 by addressing the argument of risk reduction/elimination of each hazard.

- Three goals (G3) describe that the risks from the identified hazards ("Deviation from operating area," "Loss of pipeline," and "Obstacle encounter") have been reduced as low as reasonably practicable.

- Each G3 is supported by context C2 defining the assigned severity class and strategy S4 which applies ReSonAte to estimate the level of risk from the respective hazard condition.

- The strategies and sub-goals (G4, G5, etc.) establish and support the arguments around the effectiveness of barriers, probability distributions, and risk estimates.

This assurance case effectively instantiates the provided pattern with specific details about the BlueROV2 system. Note that some goals and elements remain undeveloped as per the original pattern.