Based on the given assurance case pattern, below is the assurance case for the BlueROV2 system represented in a hierarchical tree format using dashes:

```

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

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

- G2: No intolerable risks present in the system.

- S2: Argue that risk posed by any remaining hazards is negligible (undeveloped)

- S3: Argue that no other risks have been identified (undeveloped)

- C1: Definition of "intolerable"

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

- C2: Assigned severity class is Hazard.Severity

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

- A1: Function required by BTD is available

- G4: Model BTD accurately describes possible propagation of hazard

- 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 consequence is below allowable threshold for severity class

- Sn1: Estimated risk level is attr:RiskEst

```

The expansion of placeholders and corresponding instantiation specific to the BlueROV2 system is as follows:

- In `G1`, replace `{A :: System}` with `BlueROV2 system`

- In `G3`, hazards for BlueROV2 to consider are:

- Deviation from the operating area

- Obstacle encounter

- Loss of pipeline

- In `C2`:

- Severity classes for described hazards:

- "Minor" for `Deviation from the operating area`

- "Major" for `Obstacle encounter`

- "Minor" for `Loss of pipeline`

- In `S4`, specific hazards and conditions to be considered from BlueROV2 risks are:

- “Avoidance Maneuver”

- “Emergency Stop” barriers

- In `A1`, assume function:

- "Collision avoidance function" might be inferred from BTD objects

- In `G4`, replace `{S :: BTD}` and `{R :: Hazard}` with:

- BTD is BowTie.

- Hazards are specific to BlueROV2: “Deviation from the operating area”, “Obstacle encounter”, “Loss of pipeline”

- In `G10`, consider `Severe Collisions` consequence

- In `Sn1`, risk level pertains to quantified risk like `10^-3 per collision per hour` as per provided domain insights.

Note that some elements are marked as undeveloped (e.g., S2, S3, G6, G7, G8, G9) since further development of their supporting sub-elements has not been provided.