Here is the instantiated assurance case for the BlueROV2 system using the provided pattern, represented in a hierarchical tree format:

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- 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

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

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

- G4: Model BTD accurately describes possible propagation of hazard Deviation from the operating area (uninstantiated)

- 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 (uninstantiated)

- Sn1: Estimated risk level 10^-3 per hour (uninstantiated)

- C2: Assigned severity class is Major

- A1: Function avoidance logic required by BTD is available

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

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

- G4: Model BTD accurately describes possible propagation of hazard Obstacle encounter (uninstantiated)

- 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 (uninstantiated)

- Sn1: Estimated risk level 10^-3 per hour (uninstantiated)

- C2: Assigned severity class is Major

- A1: Function obstacle detection required by BTD is available

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

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

- G4: Model BTD accurately describes possible propagation of hazard Loss of pipeline (uninstantiated)

- 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 (uninstantiated)

- Sn1: Estimated risk level 10^-3 per hour (uninstantiated)

- C2: Assigned severity class is Minor

- A1: Function command authority required by BTD is available

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This assurance case for BlueROV2 system was generated by instantiating the provided pattern. The instantiation involved replacing placeholders with specific information about the BlueROV2 system, its potential hazards, and associated risk mitigation strategies.